MCUXpresso SDK Documentation

Release 26.09.00



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Table of contents

1 FRDM-MCXA366 **3**
- 1.1 Overview . . . 3
- 1.2 SDK Introduction . . . 3
  - 1.2.1 MCUXpresso Software Development Kit (SDK) . . . 3
- 1.3 Getting Started with MCUXpresso SDK Package . . . 7
  - 1.3.1 Getting Started with MCUXpresso SDK Package . . . 7
- 1.4 Getting Started with MCUXpresso SDK GitHub . . . 63
  - 1.4.1 Getting Started with MCUXpresso SDK Repository . . . 63
- 1.5 Release Notes . . . 75
  - 1.5.1 MCUXpresso SDK Release Notes . . . 75
- 1.6 ChangeLog . . . 79
  - 1.6.1 MCUXpresso SDK Changelog . . . 79
- 1.7 Driver API Reference Manual . . . 198
- 1.8 Middleware Documentation . . . 198
  - 1.8.1 MCU Boot . . . 198
  - 1.8.2 FreeMASTER . . . 198
  - 1.8.3 FreeRTOS . . . 199
  - 1.8.4 File systemFatfs . . . 199

2 MCXA366 **201**
- 2.1 AOI: Crossbar AND/OR/INVERT Driver . . . 201
- 2.2 CACHE: LPCAC CACHE Memory Controller . . . 204
- 2.3 CDOG . . . 205
- 2.4 CRC: Cyclic Redundancy Check Driver . . . 209
- 2.5 CTIMER: Standard counter/timers . . . 212
- 2.6 DAC: Digital-to-Analog Converter Driver . . . 223
- 2.7 eDMA: Enhanced Direct Memory Access (eDMA) Controller Driver . . . 230
- 2.8 eDMA core Driver . . . 264
- 2.9 eDMA soc Driver . . . 273
- 2.10 EIM: error injection module . . . 273
- 2.11 EQDC: Enhanced Quadrature Encoder/Decoder . . . 273
- 2.12 ERM: error recording module . . . 293
- 2.13 FGPIO Driver . . . 295
- 2.14 FlexCAN: Flex Controller Area Network Driver . . . 295
- 2.15 FlexCAN Driver . . . 295
- 2.16 FlexCAN eDMA Driver . . . 350
- 2.17 FlexIO: FlexIO Driver . . . 353
- 2.18 Flexio_a-format . . . 353
- 2.19 FlexIO Camera Driver . . . 369
- 2.20 FlexIO Driver . . . 373
- 2.21 FlexIO eDMA I2S Driver . . . 393
- 2.22 FlexIO eDMA MCU Interface LCD Driver . . . 397
- 2.23 FlexIO eDMA SPI Driver . . . 399
- 2.24 FlexIO eDMA UART Driver . . . 403
- 2.25 FlexIO I2C Master Driver . . . 406
- 2.26 FlexIO I2S Driver . . . 415

2.27 FlexIO MCU Interface LCD Driver . . . 427
2.28 FlexIO SMARTDMA MCU Interface LCD Driver . . . 440
2.29 FlexIO SPI Driver . . . 443
2.30 Flexio_t-format . . . 457
2.31 FlexIO UART Driver . . . 471
2.32 FlexPWM: Enhanced Flex Pulse Width Modulator . . . 482
2.33 FREQME: Frequency Measurement . . . 541
2.34 GLIKEY . . . 541
2.35 GLIKEY . . . 541
2.36 GPIO: General-Purpose Input/Output Driver . . . 546
2.37 GPIO Driver . . . 550
2.38 I3C: I3C Driver . . . 556
2.39 I3C Common Driver . . . 558
2.40 I3C Master Driver . . . 561
2.41 I3C Master DMA Driver . . . 592
2.42 I3C Slave Driver . . . 596
2.43 I3C Slave DMA Driver . . . 610
2.44 INPUTMUX: Input Multiplexing Driver . . . 613
2.45 Common Driver . . . 614
2.46 LPADC: 12-bit SAR Analog-to-Digital Converter Driver . . . 631
2.47 Lpc_freqme . . . 652
2.48 LPCMP: Low Power Analog Comparator Driver . . . 658
2.49 LPI2C: Low Power Inter-Integrated Circuit Driver . . . 670
2.50 LPI2C Master Driver . . . 671
2.51 LPI2C Master DMA Driver . . . 687
2.52 LPI2C Slave Driver . . . 689
2.53 LPSPI: Low Power Serial Peripheral Interface . . . 701
2.54 LPSPI Peripheral driver . . . 701
2.55 LPSPI eDMA Driver . . . 725
2.56 LPTMR: Low-Power Timer . . . 733
2.57 LPUART: Low Power Universal Asynchronous Receiver/Transmitter Driver . . . 739
2.58 LPUART Driver . . . 739
2.59 LPUART eDMA Driver . . . 760
2.60 MAU: Math Accelerator Unit Driver . . . 764
2.61 MCX_CMC: Core Mode Controller Driver . . . 769
2.62 MCX_SPC: System Power Control driver . . . 782
2.63 MCX_VBAT: Smart Power Switch . . . 823
2.64 OPAMP: Operational Amplifier . . . 846
2.65 OSTIMER: OS Event Timer Driver . . . 848
2.66 PORT: Port Control and Interrupts . . . 853
2.67 PWM: Pulse Width Modulator . . . 862
2.68 RTC: Real Time Clock . . . 891
2.69 SLCD: Segment LCD Driver . . . 900
2.70 SMARTDMA: SMART DMA Driver . . . 911
2.71 MCXN SMARTDMA Firmware . . . 913
2.72 Digital Tamper . . . 916
2.73 TDET . . . 916
2.74 TRDC: Trusted Resource Domain Controller . . . 930
2.75 Trdc_core . . . 956
2.76 TRNG: True Random Number Generator . . . 972
2.77 UTICK: MictoTick Timer Driver . . . 978
2.78 WAKETIMER: WAKETIMER Driver . . . 979
2.79 WUU: Wakeup Unit driver . . . 982
2.80 WWDT: Windowed Watchdog Timer Driver . . . 988

3 Middleware **993**
3.1 Boot . . . 993
3.1.1 MCUboot in MCUXpresso SDK . . . 993

3.2 File System . . . 994
3.2.1 FatFs . . . 994
3.3 Motor Control . . . 996
3.3.1 FreeMASTER . . . 996
3.4 Multicore SDK . . . 1034
3.4.1 Quick links . . . 1034
3.4.2 Components . . . 1035

4 RTOS **1037**
4.1 FreeRTOS . . . 1037
4.1.1 FreeRTOS kernel . . . 1037
4.1.2 FreeRTOS drivers . . . 1041
4.1.3 backoffalgorithm . . . 1041
4.1.4 corehttp . . . 1041
4.1.5 corejson . . . 1041
4.1.6 coremqtt . . . 1041
4.1.7 corepkcs11 . . . 1042
4.1.8 freertos-plus-tcp . . . 1042

5 Downloads **1043**
5.1 boards . . . 1043
5.2 develop . . . 1043

Index **1045**

This documentation contains information specific to the frdmmcxa366 board.

Chapter 1

FRDM-MCXA366

1.1 Overview

FRDM-MCXA366 are compact and scalable development boards for rapid prototyping of MCX A27X MCUs. They offer industry standard headers for easy access to the MCUs I/Os, integrated open-standard serial interfaces and an on-board MCU-Link debugger. MCX A Series are high-performance, low-power microcontrollers with MAU,SmartDMA and performance efficiency.

The board is compatible with Arduino boards (Arduino UNO R3 and Arduino A4/A5), motor control boards (FRDM-MC-LVBLDC and FRDM-MC-LVPMSM), Mikroe click boards, and Pmod boards. It can be used with a wide range of development tools, including NXP MCUXpresso IDE, IAR Embedded Workbench, and Arm Keil MDK. The board is lead-free and RoHS-compliant.

For debugging the MCXA346 MCU, the FRDM-MCXA366 board uses an onboard (OB) debug probe, MCU-Link lite OB, which is based on another NXP MCU: LPC55S16



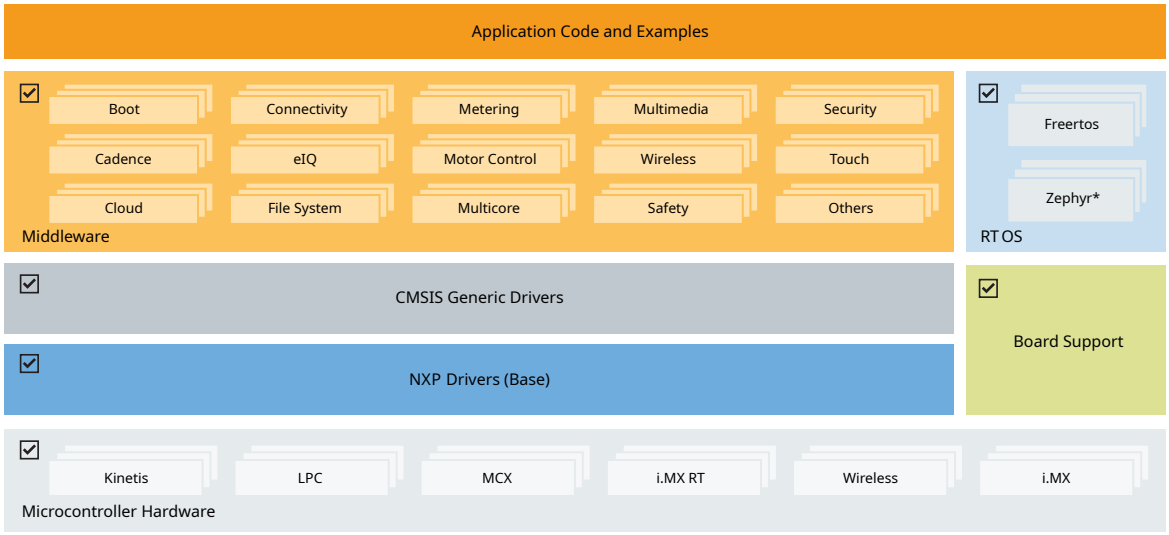
MCU device and part on board is shown below:

- Device: MCXA366
- PartNumber: MCXA366VLQ

1.2 SDK Introduction

1.2.1 MCUXpresso Software Development Kit (SDK)

The MCUXpresso SDK is a comprehensive software enablement package designed to simplify and accelerate application development with Arm® Cortex®-M based devices from NXP, including its general purpose, crossover and wireless-enabled MCUs. It includes production-grade software with integrated enabling software technologies (stacks and middleware), reference examples, and more.



*Zephyr RT OS leverages base SDK components via NXP Zepher HAL

Features

Comprehensive Driver Library

- Flexible peripheral drivers for rapid development
- Optimized for performance and code size

RTOS Integration

- FreeRTOS support with optimized configurations
- Real-time application frameworks
- Task management and scheduling examples

Middleware Components

- Connectivity stacks (USB, Ethernet, wireless, communication protocols)
- AI inference engines and neural network libraries
- Audio processing and voice recognition libraries
- Security frameworks and cryptographic libraries
- Graphics and user interface components
- Motor control and real-time control libraries
- File systems and storage solutions
- Partner middleware can be added using CMake and west manifests

Extensive Examples

- Basic peripheral use cases to full technology demonstrations
- Board-specific reference implementations

- Out-of-box Demo Applications
- Middleware component examples and integrations

Distribution Formats

MCUXpresso SDK is available in two main formats:

GitHub Repository SDK Git-based distribution hosted on GitHub for modular development, continuous updates, and collaborative workflows. The SDK uses multiple repositories managed by the Zephyr west tool to provide flexible, component-based development. See Getting Started for setup instructions.

SDK Package Downloadable packages from SDK Builder for offline development. Starting with release 25.12.00, two package versions are available:

- **Classic SDK Package**: Traditional board-specific packages with pre-configured IDE projects for MCUXpresso IDE, IAR, Keil, and other toolchains.
- **Repository-Layout SDK Package**: Board-specific packages that maintain the same structure and build system as the GitHub Repository SDK, providing offline access to the repository-based development experience. Available when selecting the ARMGCC toolchain.

Note: From version 25.12.00 onward, selecting ARMGCC downloads the Repository-Layout version; all other toolchains remain in the Classic version.

Delivery and Release

NXP integrates Coverity® Static Analysis and Black Duck Software Composition Analysis into the SDK development process to deliver secure, high-quality software.

- **Annual releases (June)** for popular products, with Long Term Support (LTS) on GitHub — back-ported security (SVE/PSIRT) and severe bug fixes for two years.
- **Quarterly releases** for NPI and recent products.
- SBOMs provided for all GitHub SDK repositories.

Release	Release Name	Maintenance
LTS	26.06.00-LTS	2 years until June 2028
Quarterly	26.09.00	None, rebase to mainline
LTS	27.06.00-LTS	2 years until June 2029

Supported platforms are listed at mcuxpresso.nxp.com/sdk-versions.

Toolchain Support

All driver examples and most application examples are provided for the following toolchains:

Toolchain	GitHub	Archive/Zip	Generated (west)	Getting Started
MCUXpresso IDE	✓	✓ eclipse	✓	*Link*
MCUXpresso for VS Code	✓	✓ CMake	N.A.	*Link*
IAR Embedded Workbench	✓	✓ EWARM	✓ EWARM	*Link*
Keil™ MDK-Arm	✓	✓ uVision	✓ uVision	*Link*
CLI GNU toolchain	✓	✓ CMake	N.A.	*Link*

Archive/Zip packages can be downloaded from SDK Builder or imported directly in VS Code and MCUXpresso IDE using the Import Wizard.

IAR and Keil projects can be generated from the GitHub SDK CMake examples using a west build command.

Repository Architecture

The SDK uses a multi-repository structure on GitHub managed by the Zephyr West Tool, enabling:

- **Modular Organization**: Drivers, RTOS, middleware, and examples in separate repositories
- **Customizable Manifests**: Targeted setups for specific requirements
- **Selective Downloads**: Include only needed components
- **Independent Updates**: Component-level version control
- **Scalable Integration**: Easy addition of new repository components

Support and Resources

Community Support

- Open GitHub issues and discussions for questions and contributions
- MCUXpresso SDK Community Forum
- MCUXpresso Software and Tools Forum

Documentation

- Comprehensive guides and API documentation online

Technical Support

- NXP Support for commercial development assistance

SDK Product Page

- MCUXpresso SDK on NXP.com

Trainings

- MCUXpresso Training Hub
- MCUXpresso SDK Curriculum

1.3 Getting Started with MCUXpresso SDK Package

1.3.1 Getting Started with MCUXpresso SDK Package

Starting with version 25.09.00, MCUXpresso SDK introduced two package versions for offline development:

- **Classic SDK Package**: Traditional board-specific packages with pre-configured IDE projects for MCUXpresso IDE, IAR, Keil, and other toolchains.
- **Repository-Layout SDK Package**: Board-specific packages that maintain the same structure and build system as the GitHub Repository SDK, providing offline access to the repository SDK development experience. Available when selecting the ARMGCC toolchain.

From version 25.12.00 onward:

- When you select ARMGCC, the SDK download will use the Repository-Layout version.
- For all other toolchains, the SDK download will remain in the Classic version.

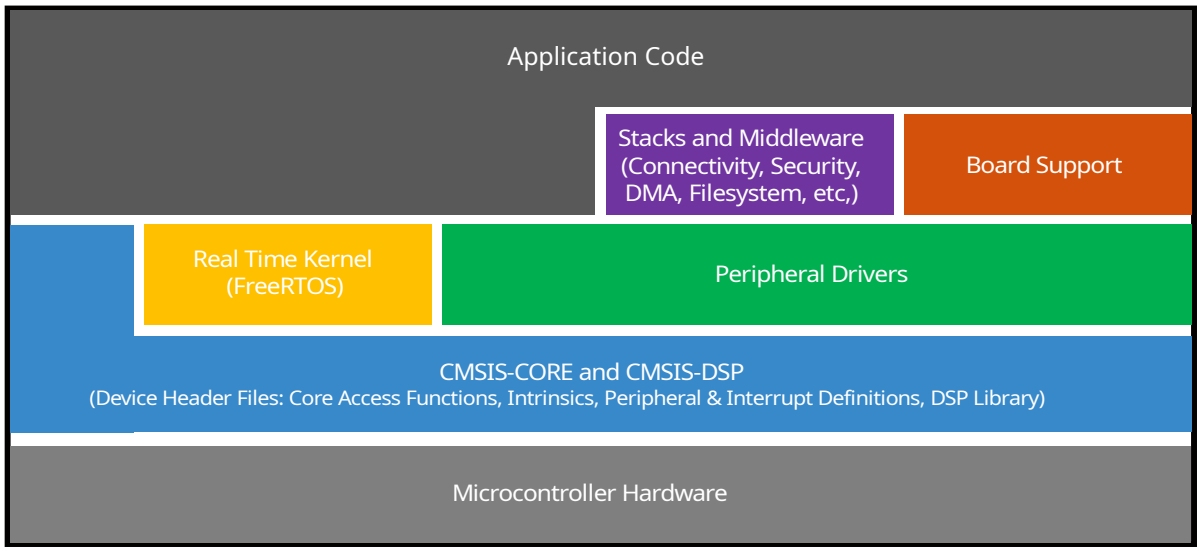
Note: The Repository-Layout SDK package was first introduced in version 25.09.00, but initially only for MCXW23x platforms.

Classic SDK Package

Overview The NXP MCUXpresso software and tools offer comprehensive development solutions designed to optimize, ease, and help accelerate embedded system development of applications based on general purpose, crossover, and Bluetooth-enabled MCUs from NXP. The MCUXpresso SDK includes a flexible set of peripheral drivers designed to speed up and simplify development of embedded applications. Along with the peripheral drivers, the MCUXpresso SDK provides an extensive and rich set of example applications covering everything from basic peripheral use case examples to full demo applications. The MCUXpresso SDK contains optional RTOS integrations such as FreeRTOS and Azure RTOS, and various other middleware to support rapid development.

For supported toolchain versions, see *MCUXpresso SDK Release Notes* (document MCUXSDKRN).

For more details about MCUXpresso SDK, see MCUXpresso Software Development Kit (SDK).



MCUXpresso SDK board support package folders MCUXpresso SDK board support package provides example applications for NXP development and evaluation boards for Arm Cortex-M cores including Freedom, Tower System, and LPCXpresso boards. Board support packages are found inside the top-level boards folder and each supported board has its own folder (an MCUXpresso SDK package can support multiple boards). Within each <board_name> folder, there are various subfolders to classify the type of examples it contains. These include (but are not limited to):

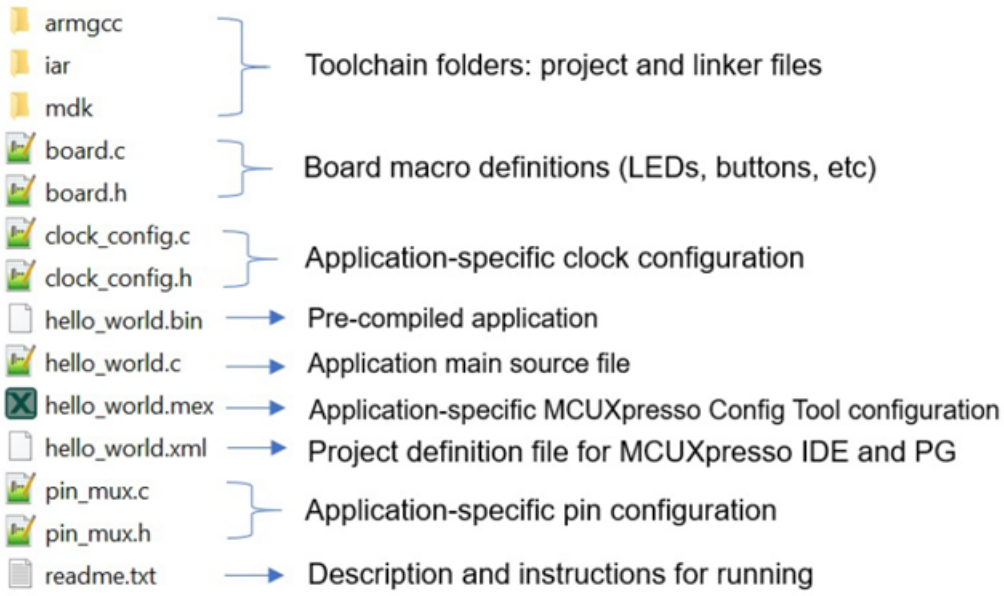
- cmsis_driver_examples: Simple applications intended to show how to use CMSIS drivers.
- demo_apps: Full-featured applications that highlight key functionality and use cases of the target MCU. These applications typically use multiple MCU peripherals and may leverage stacks and middleware.
- driver_examples: Simple applications that show how to use the MCUXpresso SDK's peripheral drivers for a single use case. These applications typically only use a single peripheral but there are cases where multiple peripherals are used (for example, SPI conversion using DMA).
- emwin_examples: Applications that use the emWin GUI widgets.
- rtos_examples: Basic FreeRTOS OS examples that show the use of various RTOS objects (semaphores, queues, and so on) and interfaces with the MCUXpresso SDK's RTOS drivers
- usb_examples: Applications that use the USB host/device/OTG stack.

Example application structure

This section describes how the various types of example applications interact with the other components in the MCUXpresso SDK. To get a comprehensive understanding of all MCUXpresso SDK components and folder structure, see *MCUXpresso SDK API Reference Manual*.

Each <board_name> folder in the boards directory contains a comprehensive set of examples that are relevant to that specific piece of hardware. Although we use the hello_world example (part of the demo_apps folder), the same general rules apply to any type of example in the <board_name> folder.

In the hello_world application folder you see the following contents:



All files in the application folder are specific to that example, so it is easy to copy and paste an existing example to start developing a custom application based on a project provided in the MCUXpresso SDK.

Locating example application source files

When opening an example application in any of the supported IDEs, various source files are referenced. The MCUXpresso SDK devices folder is the central component to all example applications. It means that the examples reference the same source files and, if one of these files is modified, it could potentially impact the behavior of other examples.

The main areas of the MCUXpresso SDK tree used in all example applications are:

- devices/<device_name>: The device's CMSIS header file, MCUXpresso SDK feature file, and a few other files
- devices/<device_name>/cmsis_drivers: All the CMSIS drivers for your specific MCU
- devices/<device_name>/drivers: All of the peripheral drivers for your specific MCU
- devices/<device_name>/<tool_name>: Toolchain-specific startup code, including vector table definitions
- devices/<device_name>/utilities: Items such as the debug console that are used by many of the example applications
- devices/<devices_name>/project: Project template used in CMSIS PACK new project creation

For examples containing middleware/stacks or an RTOS, there are references to the appropriate source code. Middleware source files are located in the middleware folder and RTOSes are in the rtos folder. The core files of each of these are shared, so modifying one could have potential impacts on other projects that depend on that file.

Run a demo using MCUXpresso IDE

Note: Ensure that the MCUXpresso IDE toolchain is included when generating the MCUXpresso SDK package.

This section describes the steps required to configure MCUXpresso IDE to build, run, and debug example applications. The hello_world demo application targeted for the hardware platform is used as an example, though these steps can be applied to any example application in the MCUXpresso SDK.

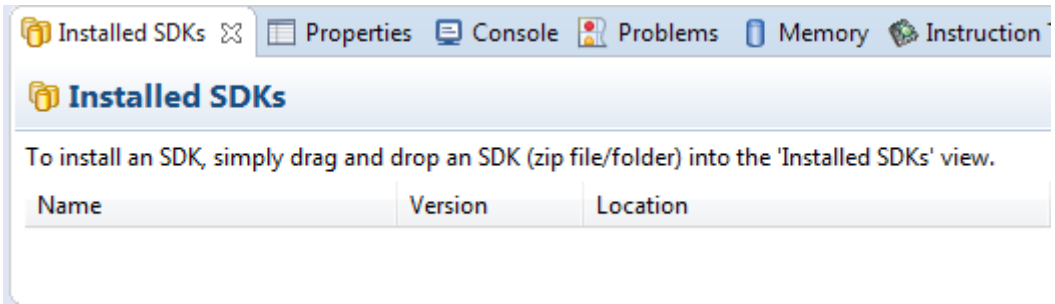
Select the workspace location

Every time MCUXpresso IDE launches, it prompts the user to select a workspace location. MCUXpresso IDE is built on top of Eclipse which uses workspace to store information about its current configuration, and in some use cases, source files for the projects are in the workspace. The location of the workspace can be anywhere, but it is recommended that the workspace be located outside the MCUXpresso SDK tree.

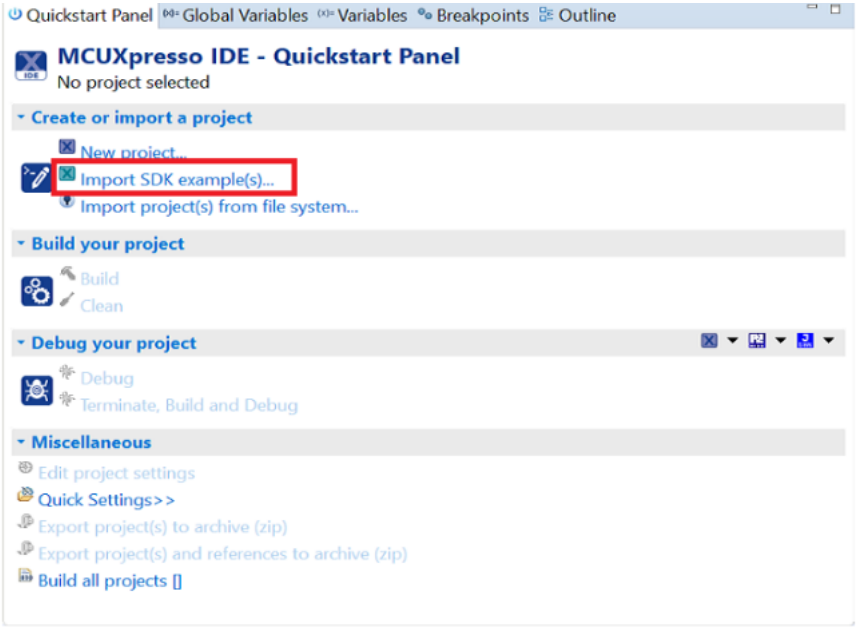
Build an example application

To build an example application, follow these steps.

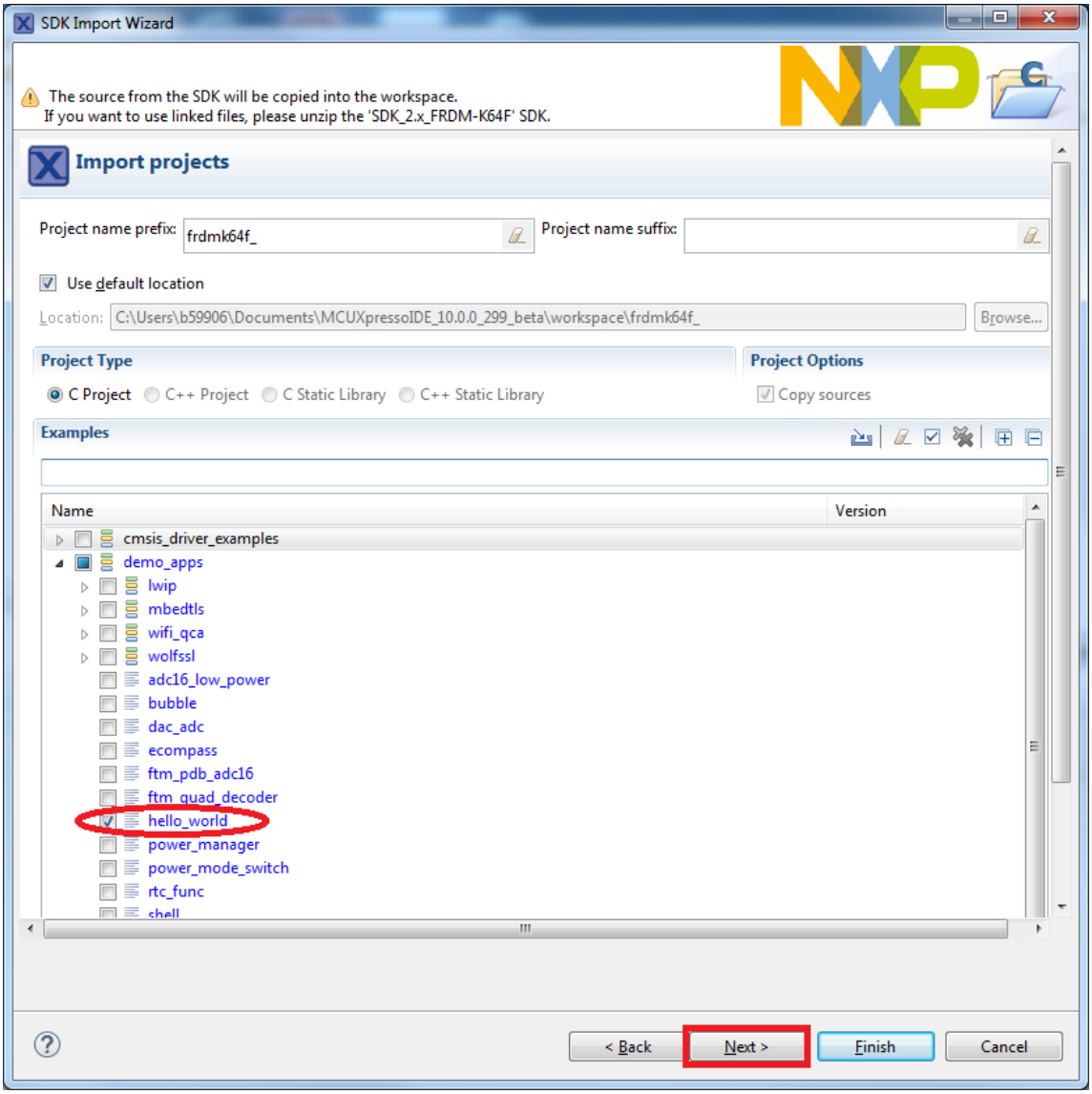
1. Drag and drop the SDK zip file into the **Installed SDKs** view to install an SDK. In the window that appears, click **OK** and wait until the import has finished.



2. On the **Quickstart Panel**, click **Import SDK example(s)...**.



3. Expand the demo_apps folder and select hello_world.
4. Click **Next.**



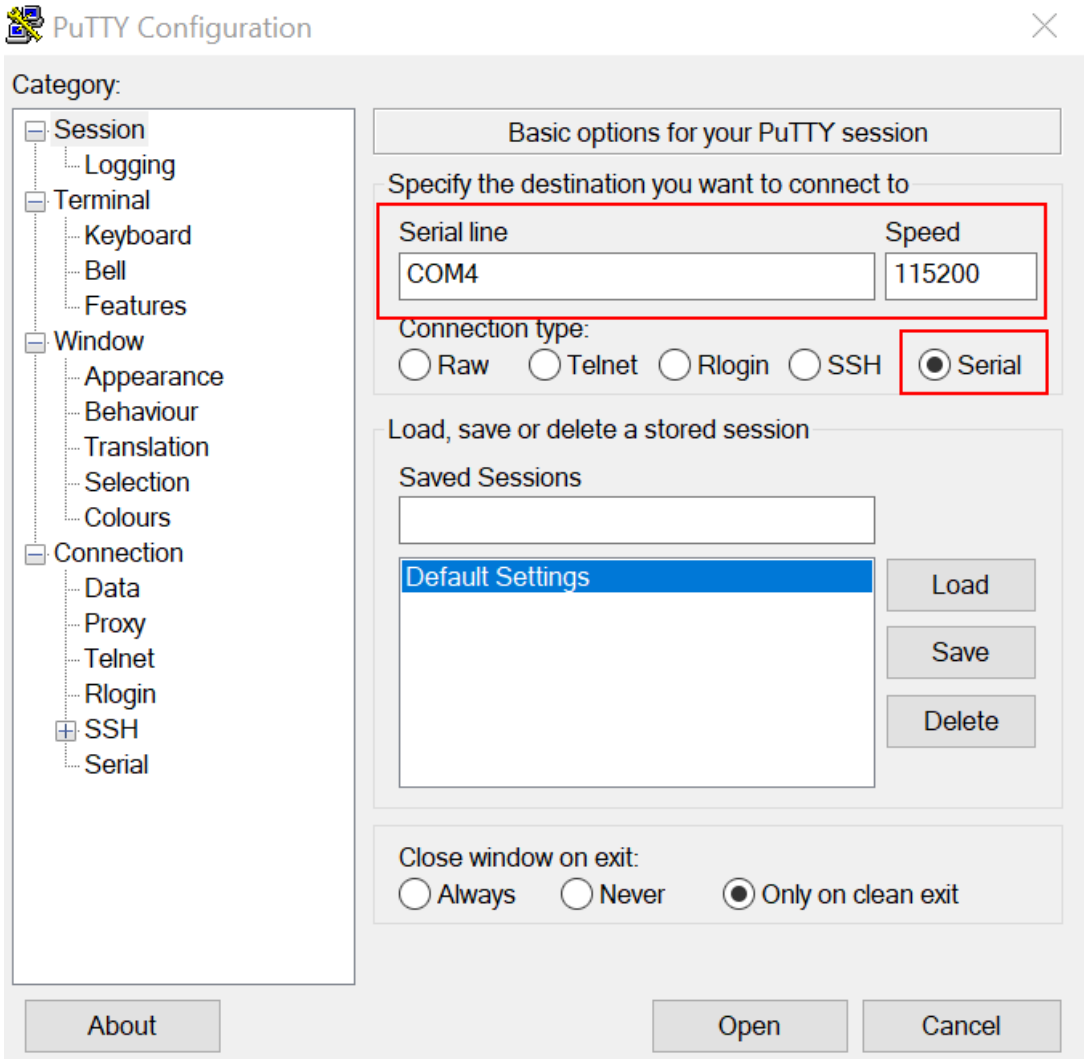
5. Ensure **Redlib: Use floating-point version of printf** is selected if the example prints floating-point numbers on the terminalfor demo applications such as adc_basic, adc_burst, adc_dma, and adc_interrupt. Otherwise, it is not necessary to select this option. Then, click **Finish**.

Run an example application

For more information on debug probe support in the MCUXpresso IDE, see community.nxp.com.

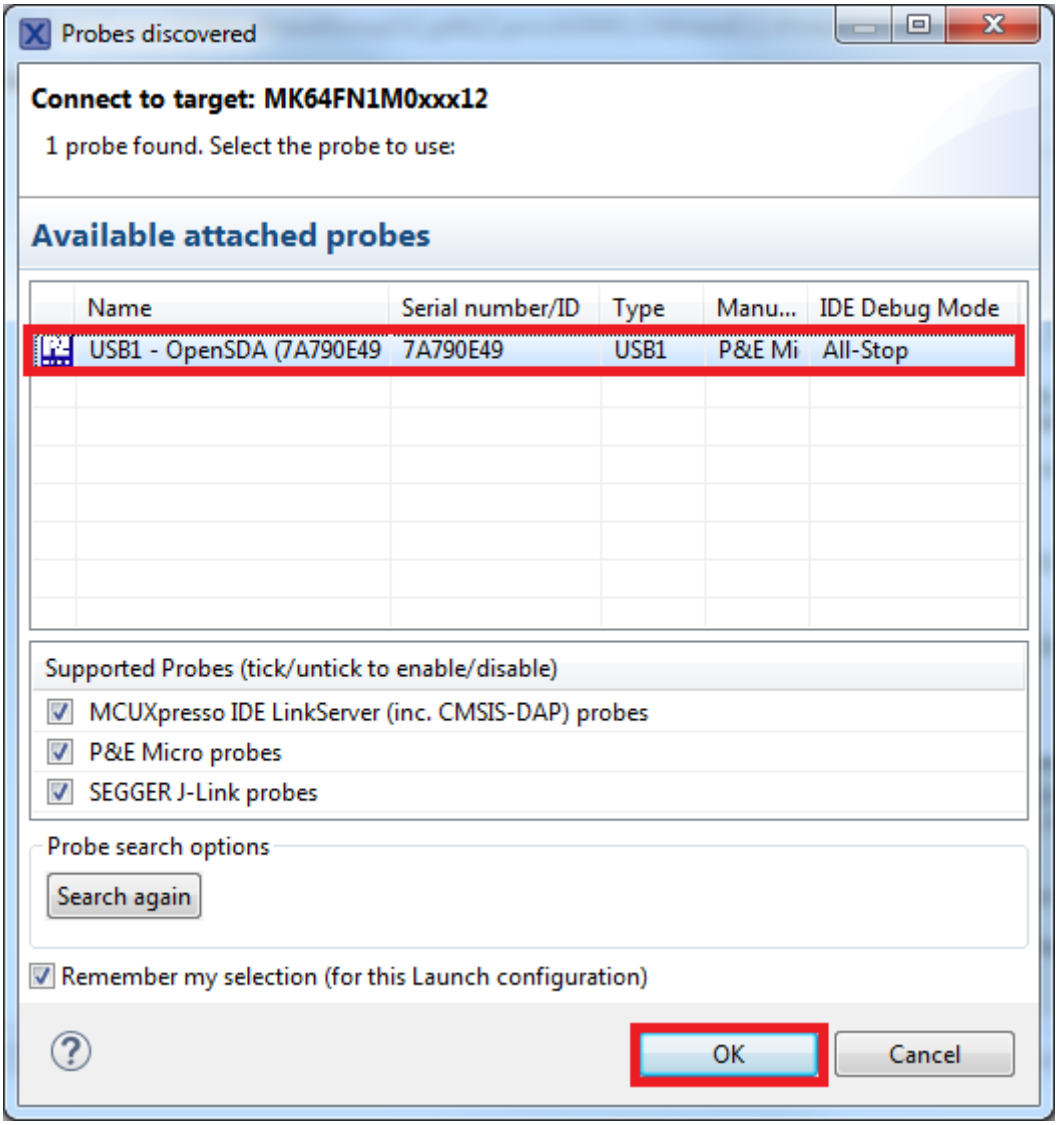
To download and run the application, perform the following steps:

1. Ensure the host driver for the debugger firmware has been installed.
2. Connect the development platform to your PC via a USB cable.
3. Open the terminal application on the PC, such as PuTTY or TeraTerm, and connect to the debug serial port number (to determine the COM port number, see *How to determine COM port*. Configure the terminal with these settings:
    1. 115200 or 9600 baud rate, depending on your board (reference BOARD_DEBUG_UART_BAUDRATE variable in board.h file)
    2. No parity
    3. 8 data bits



4. 1 stop bit

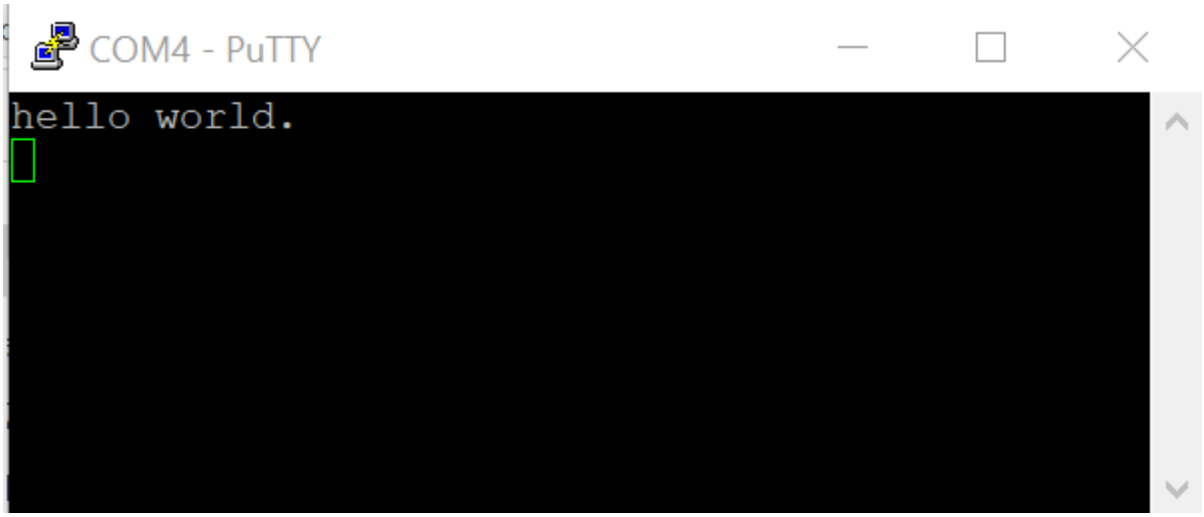
4. On the **Quickstart Panel**, click **Debug** to launch the debug session.
5. The first time you debug a project, the **Debug Emulator Selection** dialog is displayed, showing all supported probes that are attached to your computer. Select the probe through which you want to debug and click **OK**. (For any future debug sessions, the stored probe selection is automatically used, unless the probe cannot be found.)



6. The application is downloaded to the target and automatically runs to main().
7. Start the application by clicking **Resume**.



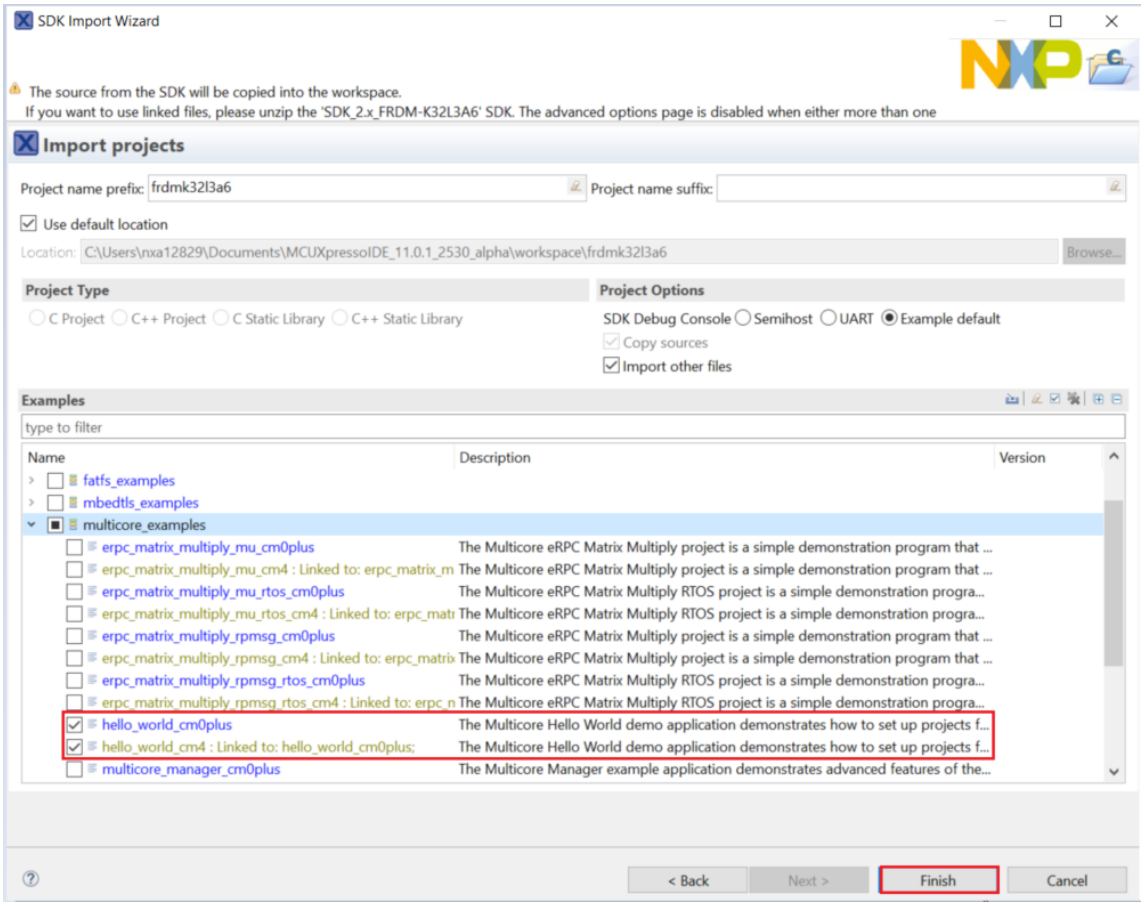
The hello_world application is now running and a banner is displayed on the terminal. If not, check your terminal settings and connections.



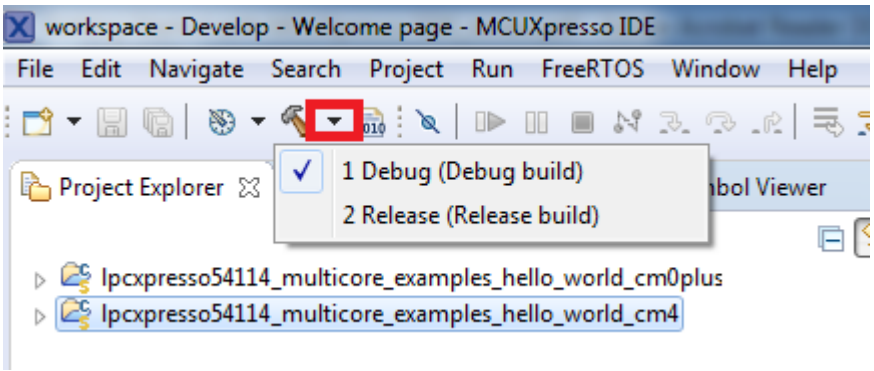
Build a multicore example application

This section describes the steps required to configure MCUXpresso IDE to build, run, and debug multicore example applications. The following steps can be applied to any multicore example application in the MCUXpresso SDK. Here, the dual-core version of hello_world example application targeted for the LPCXpresso54114 hardware platform is used as an example.

1. Multicore examples are imported into the workspace in a similar way as single core applications, explained in **Build an example application**. When the SDK zip package for LPCXpresso54114 is installed and available in the **Installed SDKs** view, click **Import SDK example(s)...** on the Quickstart Panel. In the window that appears, expand the **LPCxx** folder and select **LPC54114J256**. Then, select **lpcxpresso54114** and click **Next**.
2. Expand the multicore_examples/hello_world folder and select **cm4**. The cm0plus counterpart project is automatically imported with the cm4 project, because the multicore examples are linked together and there is no need to select it explicitly. Click **Finish**.

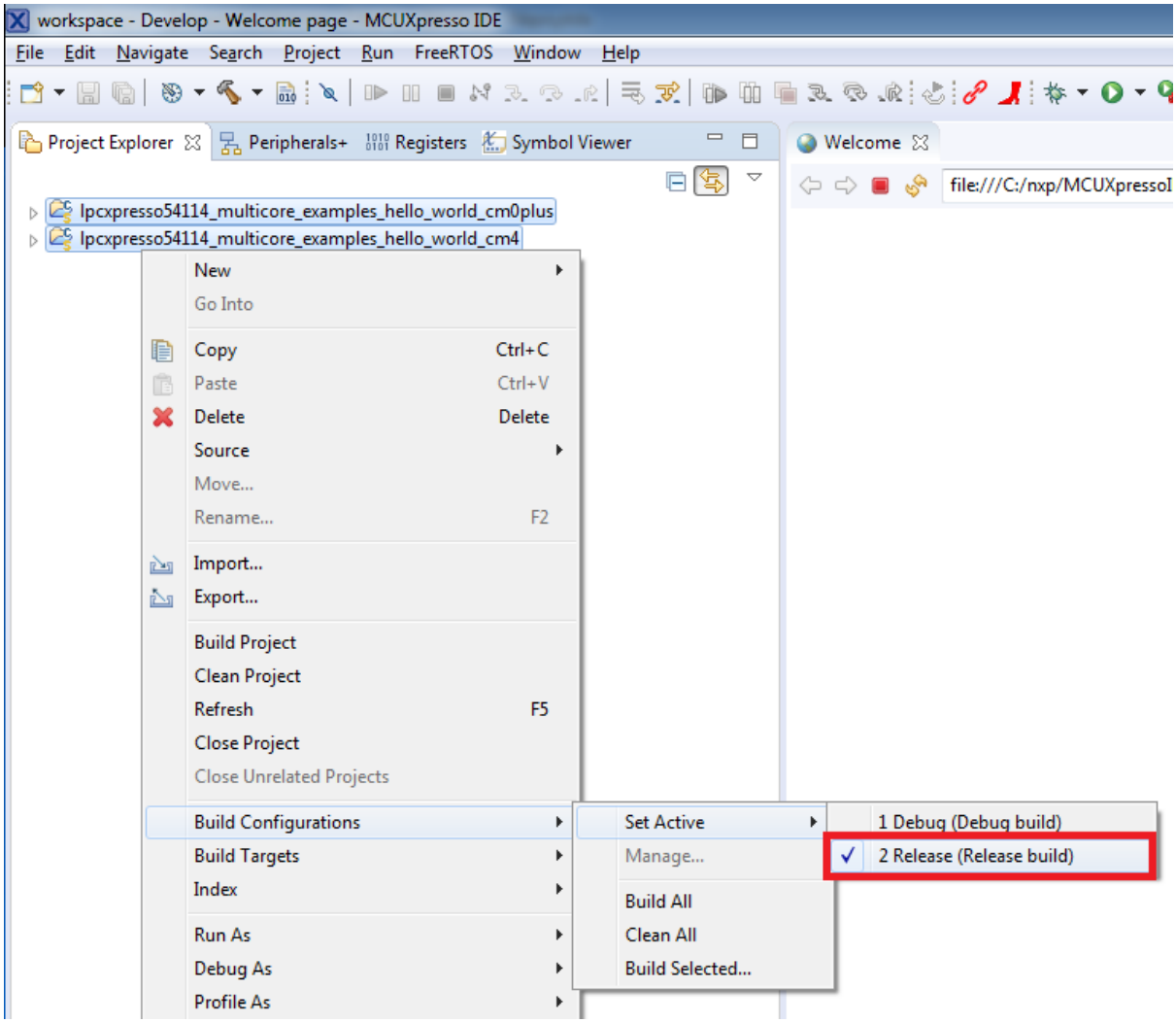


3. Now, two projects should be imported into the workspace. To start building the multicore application, highlight the lpcxpresso54114_multicore_examples_hello_world_cm4 project (multicore master project) in the Project Explorer. Then choose the appropriate build target, **Debug** or **Release**, by clicking the downward facing arrow next to the hammer icon, as shown in the figure. For this example, select **Debug**.



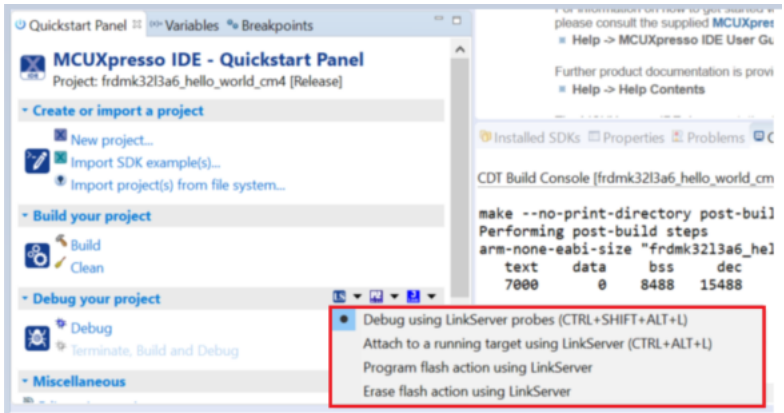
The project starts building after the build target is selected. Because of the project reference settings in multicore projects, triggering the build of the primary core application (cm4) also causes the referenced auxiliary core application (cm0plus) to build.

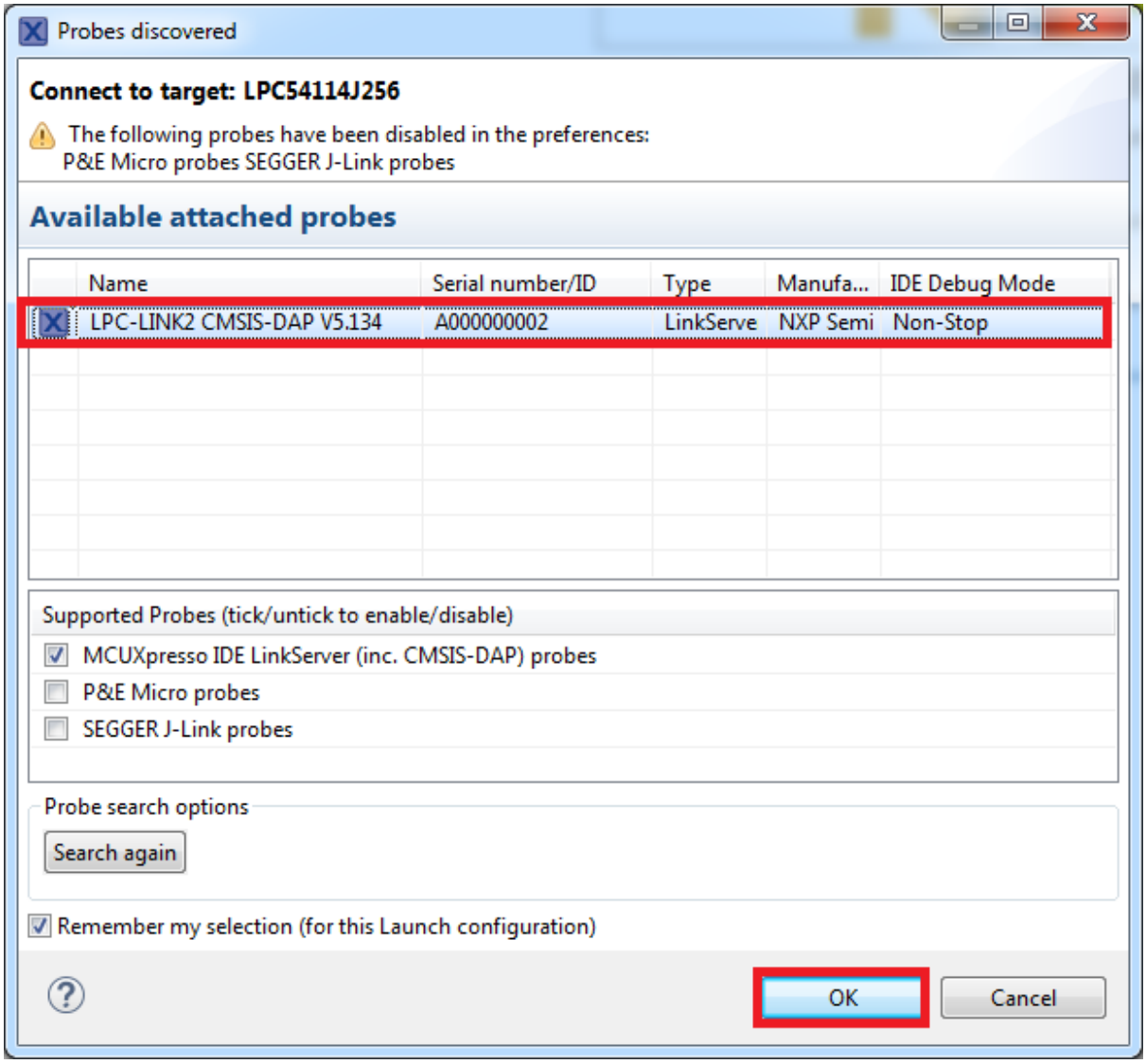
Note: When the **Release** build is requested, it is necessary to change the build configuration of both the primary and auxiliary core application projects first. To do this, select both projects in the Project Explorer view and then right click which displays the context-sensitive menu. Select **Build Configurations** -> **Set Active** -> **Release**. This alternate navigation using the menu item is **Project** -> **Build Configuration** -> **Set Active** -> **Release**. After switching to the **Release** build configuration, the build of the multicore example can be started by triggering the primary core application (cm4) build.

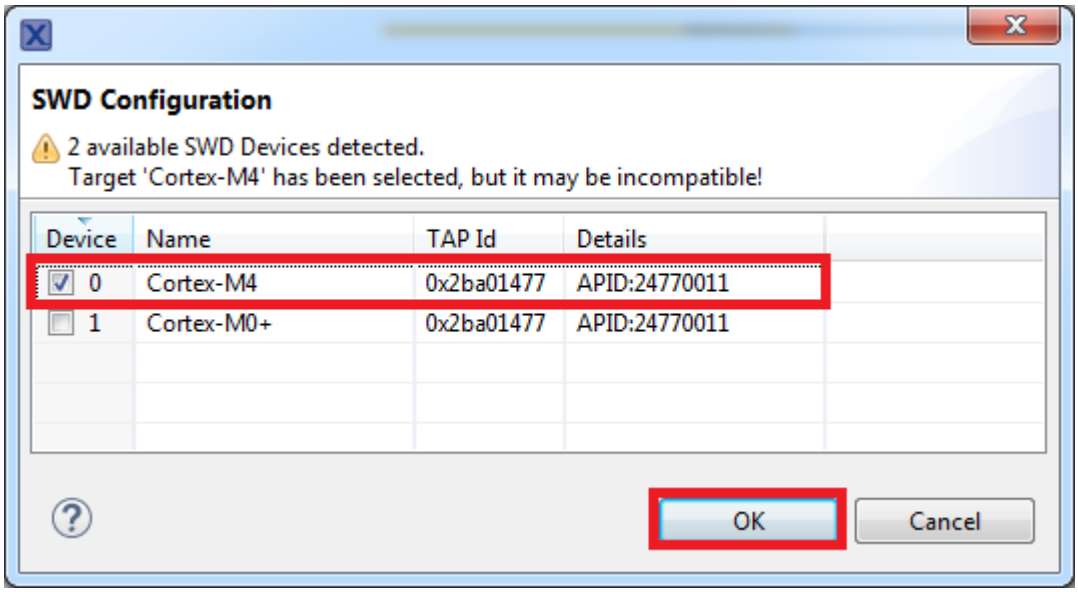


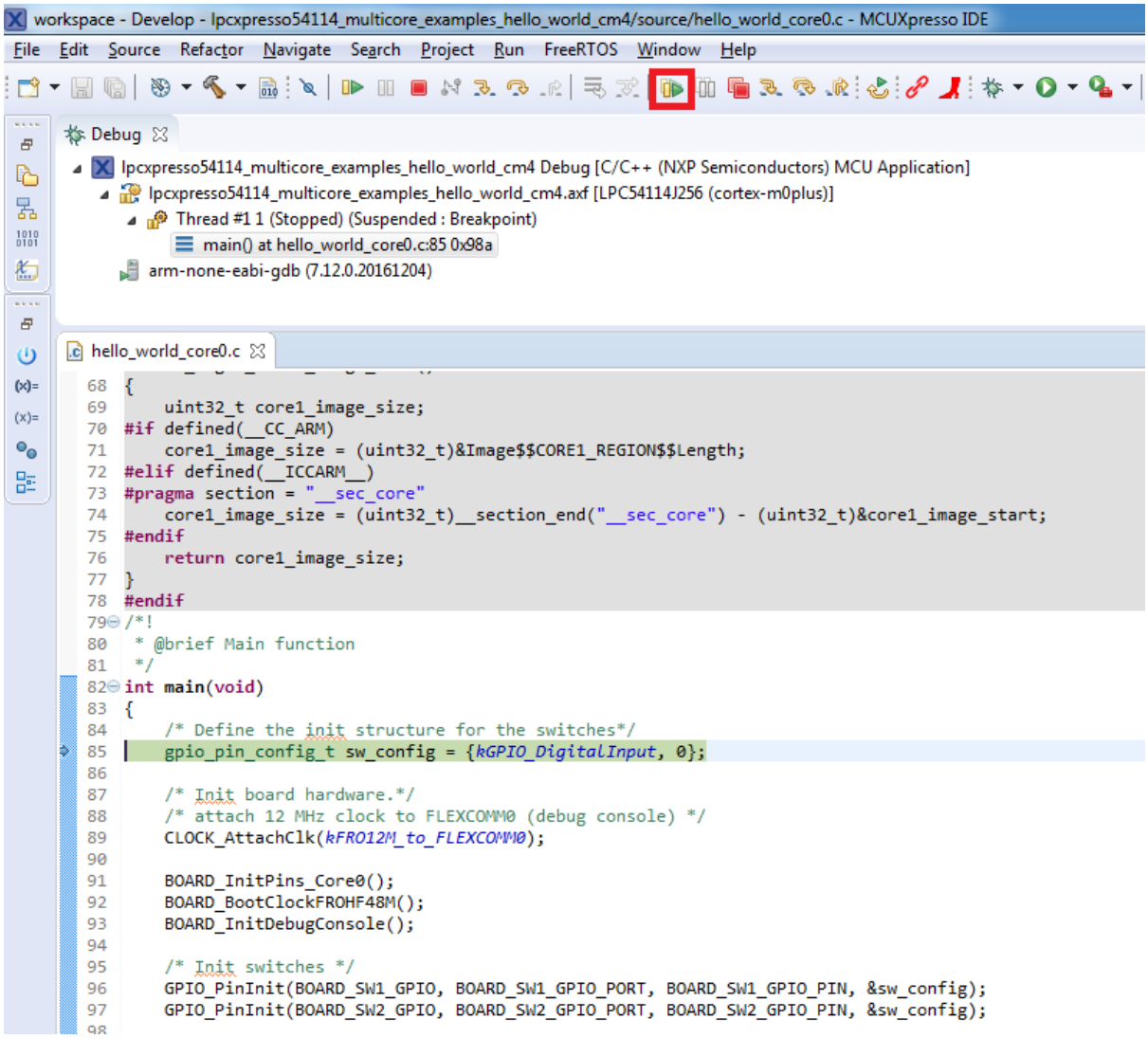
Run a multicore example application

The primary core debugger handles flashing of both the primary and the auxiliary core applications into the SoC flash memory. To download and run the multicore application, switch to the primary core application project and perform all steps as described in **Run an example application**. These steps are common for both single-core applications and the primary side of dual-core applications, ensuring both sides of the multicore application are properly loaded and started. However, there is one additional dialogue that is specific to multicore examples which requires selecting the target core. See the following figures as reference.

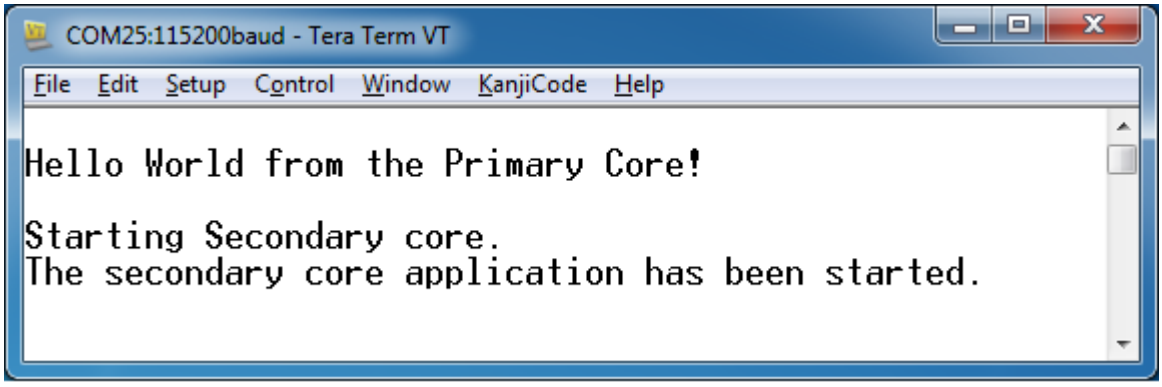



Probes discovered
Connect to target: LPC54114J256
The following probes have been disabled in the preferences:
P&E Micro probes SEGGER J-Link probes
Available attached probes
Name
Serial number/ID
Type
Manufa...
IDE Debug Mode
LPC-LINK2 CMSIS-DAP V5.134
A000000002
LinkServe
NXP Semi
Non-Stop
Supported Probes (tick/untick to enable/disable)
MCUXpresso IDE LinkServer (inc. CMSIS-DAP) probes
P&E Micro probes
SEGGER J-Link probes
Probe search options
Search again
Remember my selection (for this Launch configuration)
OK
Cancel


SWD Configuration
2 available SWD Devices detected.
Target 'Cortex-M4' has been selected, but it may be incompatible!
Device
Name
TAP Id
Details
0
Cortex-M4
0x2ba01477
APID:24770011
1
Cortex-M0+
0x2ba01477
APID:24770011
OK
Cancel

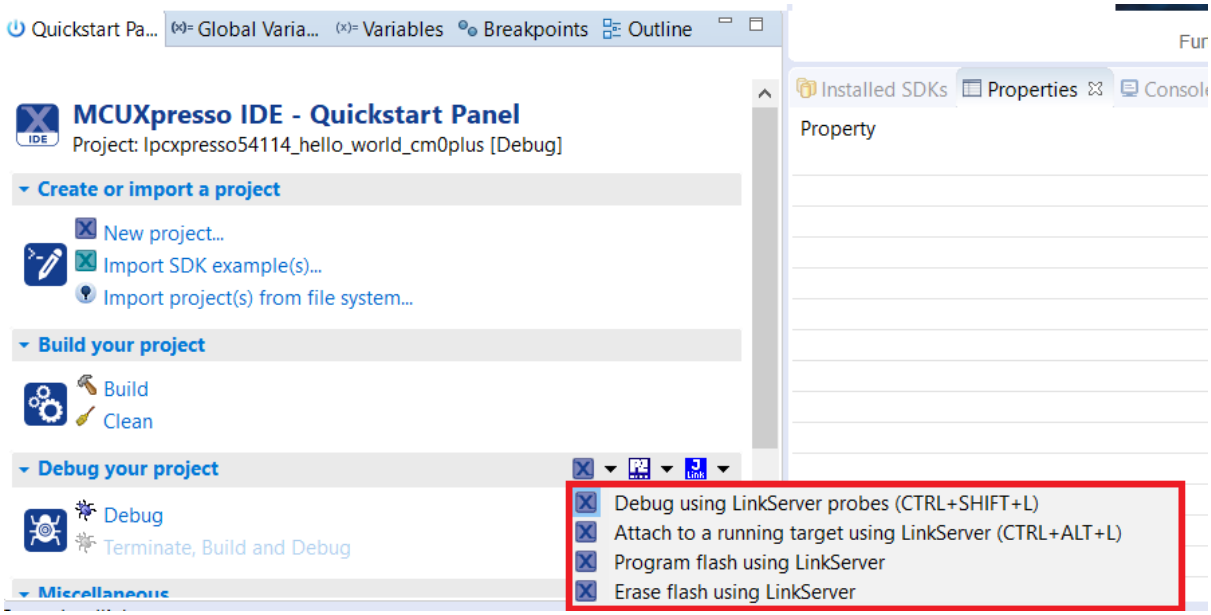


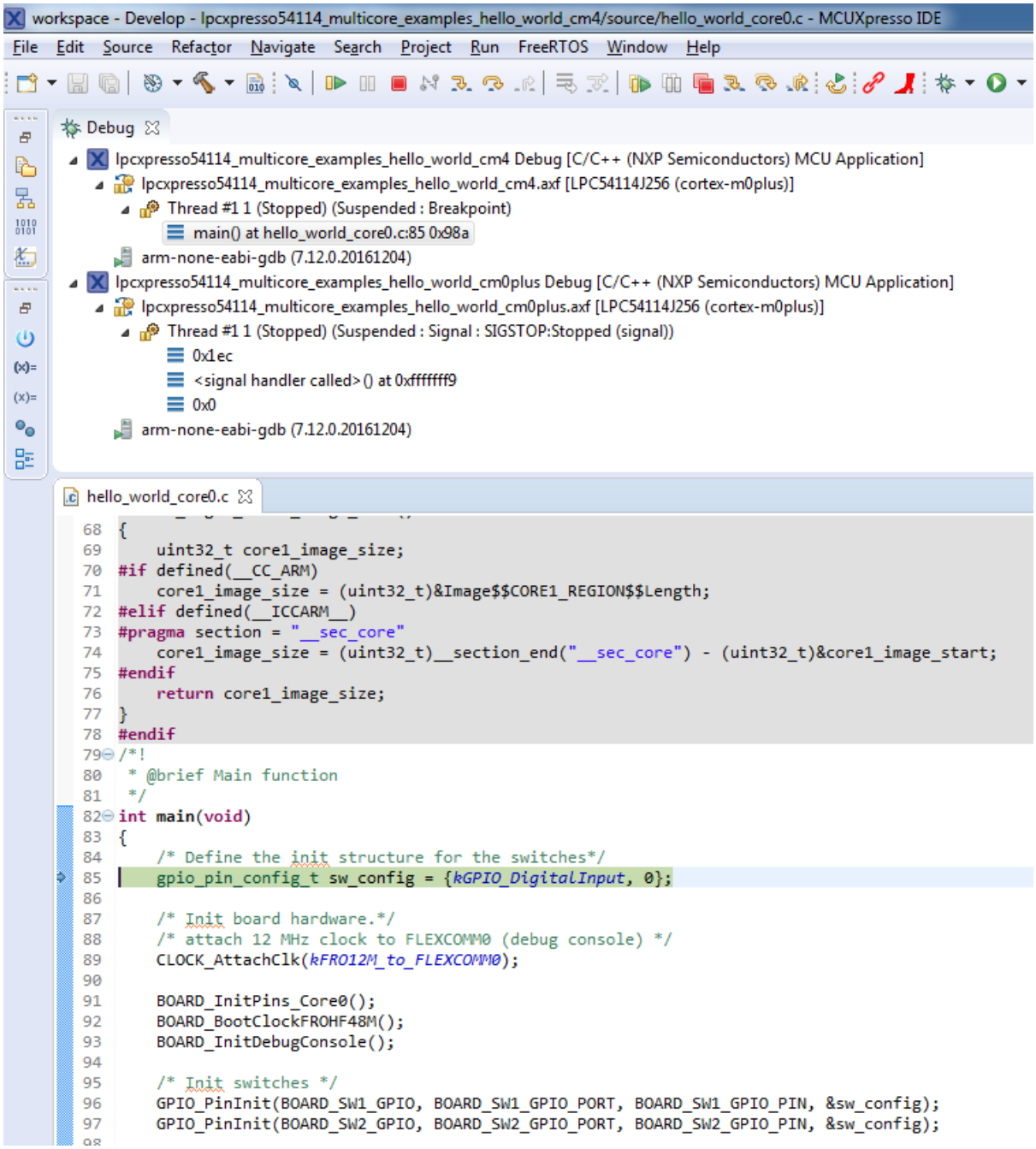
After clicking the “Resume All Debug sessions” button, the hello_world multicore application runs and a banner is displayed on the terminal. If this is not the case, check your terminal settings and connections.



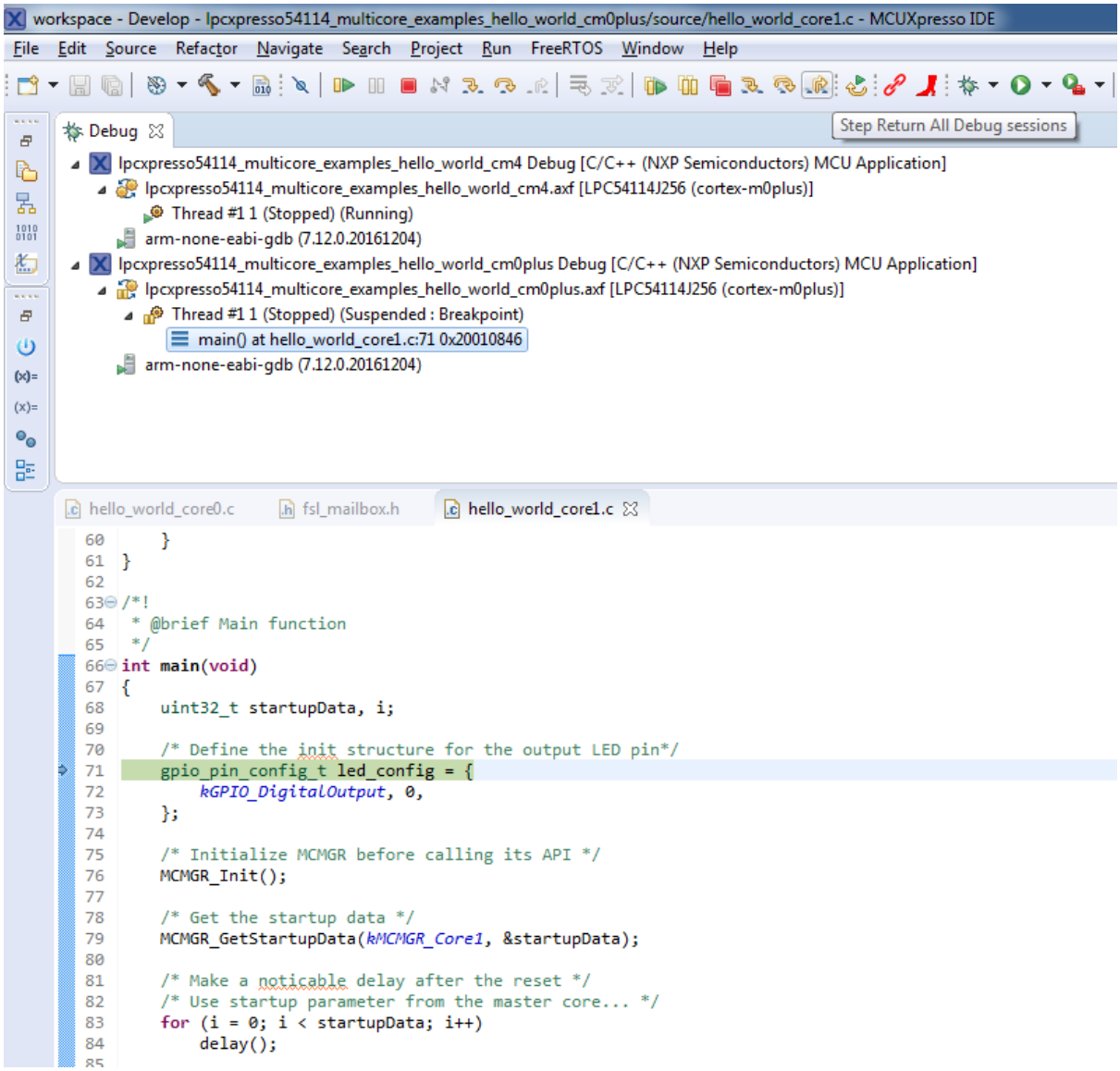
An LED controlled by the auxiliary core starts flashing, indicating that the auxiliary core has been released from the reset and running correctly. It is also possible to debug both sides of the multicore application in parallel. After creating the debug session for the primary core, perform same steps also for the auxiliary core application. Highlight the lpcxpresso54114_multicore_examples_hello_world_cm0plus project (multicore slave project) in the Project Explorer. On the Quickstart Panel, click “Debug ‘lpcxpresso54114_multicore_examples_hello_world_cm0plus’ [Debug]” to launch the second debug

session.

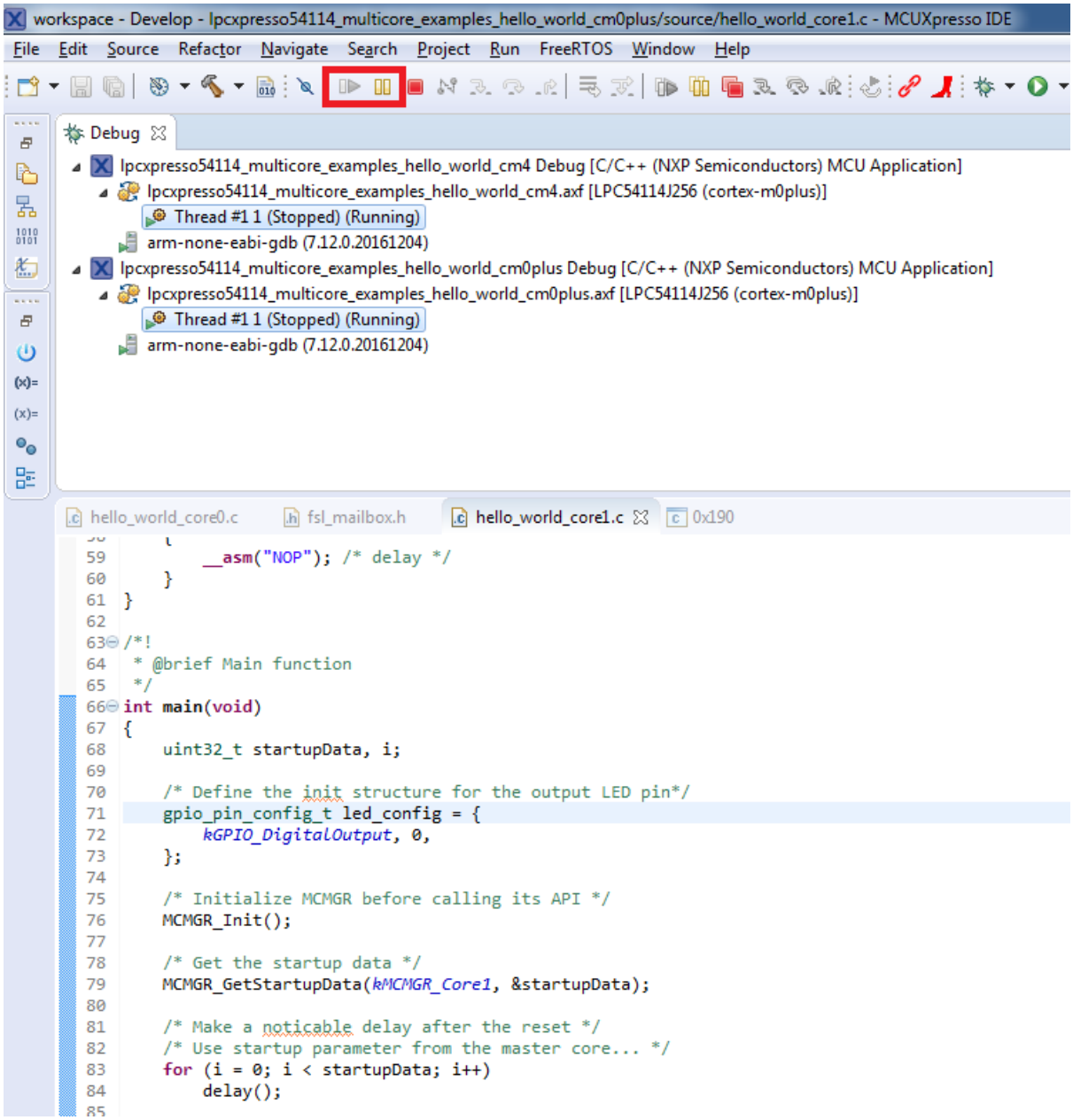

Quickstart Pa...
Global Varia...
Variables
Breakpoints
Outline
MCUXpresso IDE - Quickstart Panel
Project: lpcxpresso54114_hello_world_cm0plus [Debug]
Create or import a project
New project...
Import SDK example(s)...
Import project(s) from file system...
Build your project
Build
Clean
Debug your project
Debug
Terminate, Build and Debug
Miscellaneous
Installed SDKs
Properties
Property
Debug using LinkServer probes (CTRL+SHIFT+L)
Attach to a running target using LinkServer (CTRL+ALT+L)
Program flash using LinkServer
Erase flash using LinkServer

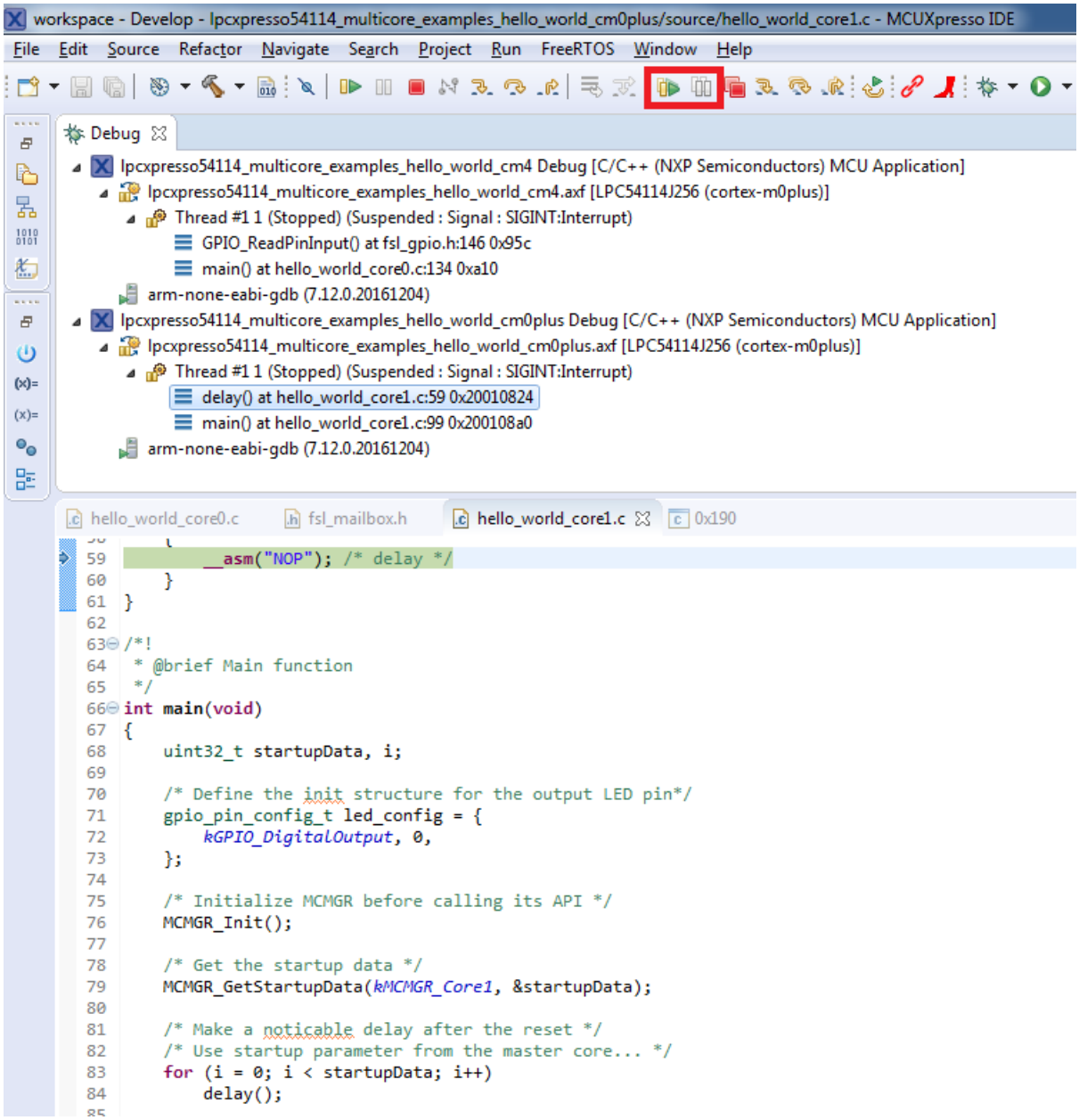


Now, the two debug sessions should be opened, and the debug controls can be used for both debug sessions depending on the debug session selection. Keep the primary core debug session selected by clicking the “Resume” button. The hello_world multicore application then starts running. The primary core application starts the auxiliary core application during runtime, and the auxiliary core application stops at the beginning of the main() function. The debug session of the auxiliary core application is highlighted. After clicking the “Resume” button, it is applied to the auxiliary core debug session. Therefore, the auxiliary core application continues its execution.



At this point, it is possible to suspend and resume individual cores independently. It is also possible to make synchronous suspension and resumption of both the cores. This is done either by selecting both opened debug sessions (multiple selections) and clicking the “Suspend” / “Resume” control button, or just using the “Suspend All Debug sessions” and the “Resume All Debug sessions” buttons.

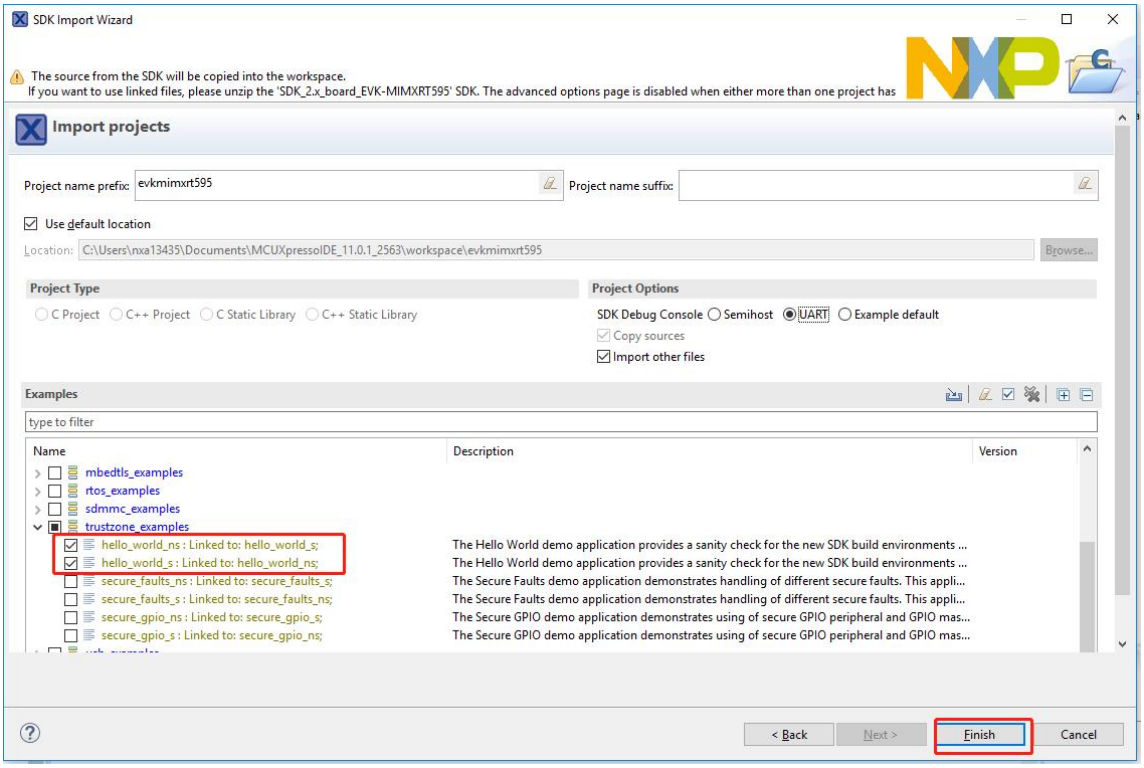

workspace - Develop - lpcxpresso54114_multicore_examples_hello_world_cm0plus/source/hello_world_core1.c - MCUXpresso IDE
File Edit Source Refactor Navigate Search Project Run FreeRTOS Window Help
Debug
lpcxpresso54114_multicore_examples_hello_world_cm4 Debug [C/C++ (NXP Semiconductors) MCU Application]
lpcxpresso54114_multicore_examples_hello_world_cm4.axf [LPC54114J256 (cortex-m0plus)]
Thread #1 1 (Stopped) (Running)
arm-none-eabi-gdb (7.12.0.20161204)
lpcxpresso54114_multicore_examples_hello_world_cm0plus Debug [C/C++ (NXP Semiconductors) MCU Application]
lpcxpresso54114_multicore_examples_hello_world_cm0plus.axf [LPC54114J256 (cortex-m0plus)]
Thread #1 1 (Stopped) (Running)
arm-none-eabi-gdb (7.12.0.20161204)
hello_world_core0.c
fsl_mailbox.h
hello_world_core1.c
0x190
59 __asm("NOP"); /* delay */
60 }
61 }
62
63 /*!
64 * @brief Main function
65 */
66 int main(void)
67 {
68 uint32_t startupData, i;
69
70 /* Define the init structure for the output LED pin*/
71 gpio_pin_config_t led_config = {
72 kGPIO_DigitalOutput, 0,
73 };
74
75 /* Initialize MCMGR before calling its API */
76 MCMGR_Init();
77
78 /* Get the startup data */
79 MCMGR_GetStartupData(kMCMGR_Core1, &startupData);
80
81 /* Make a noticable delay after the reset */
82 /* Use startup parameter from the master core... */
83 for (i = 0; i < startupData; i++)
84 delay();
85



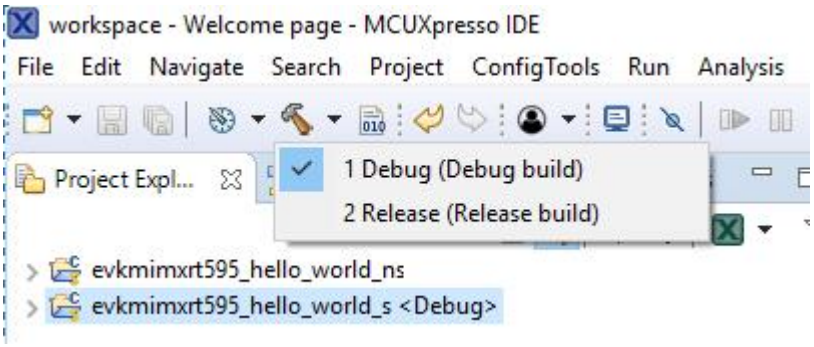
Build a TrustZone example application

This section describes the steps required to configure MCUXpresso IDE to build, run, and debug TrustZone example applications. The TrustZone version of the hello_world example application targeted for the MIMXRT595-EVK hardware platform is used as an example, though these steps can be applied to any TrustZone example application in the MCUXpresso SDK.

1. TrustZone examples are imported into the workspace in a similar way as single core applications. When the SDK zip package for MIMXRT595-EVK is installed and available in the **Installed SDKs** view, click **Import SDK example(s)...** on the Quickstart Panel. In the window that appears, expand the **MIMXRT500** folder and select **MIMXRT595S**. Then, select **evkmimxrt595** and click **Next**.
2. Expand the trustzone_examples/ folder and select hello_world_s. Because TrustZone examples are linked together, the non-secure project is automatically imported with the secure project, and there is no need to select it explicitly. Then, click **Finish**.

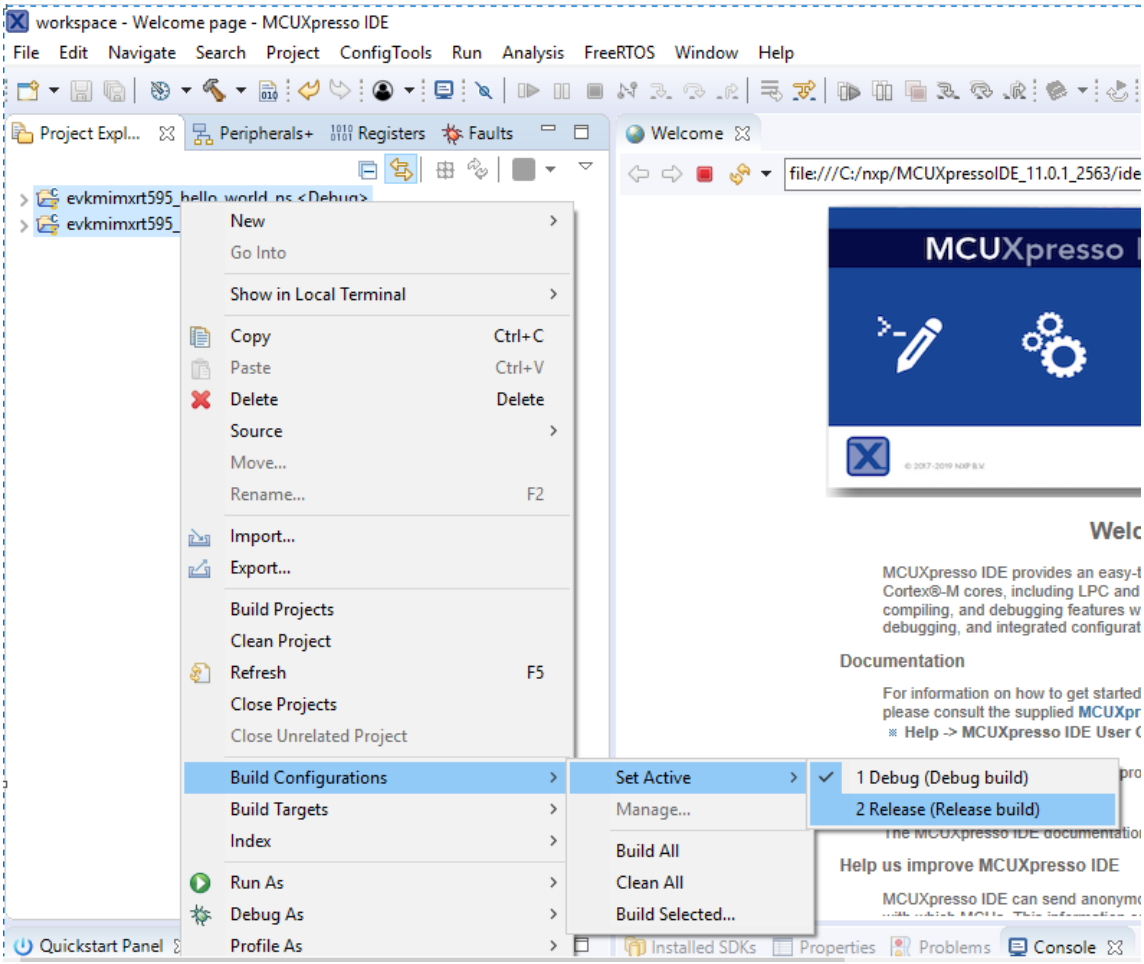


3. Now, two projects should be imported into the workspace. To start building the TrustZone application, highlight the evkmimxrt595_hello_world_s project (TrustZone master project) in the Project Explorer. Then, choose the appropriate build target, **Debug** or **Release**, by clicking the downward facing arrow next to the hammer icon, as shown in following figure. For this example, select the **Debug** target.



The project starts building after the build target is selected. It is requested to build the application for the secure project first, because the non-secure project must know the secure project since CMSE library when running the linker. It is not possible to finish the non-secure project linker when the secure project since CMSE library is not ready.

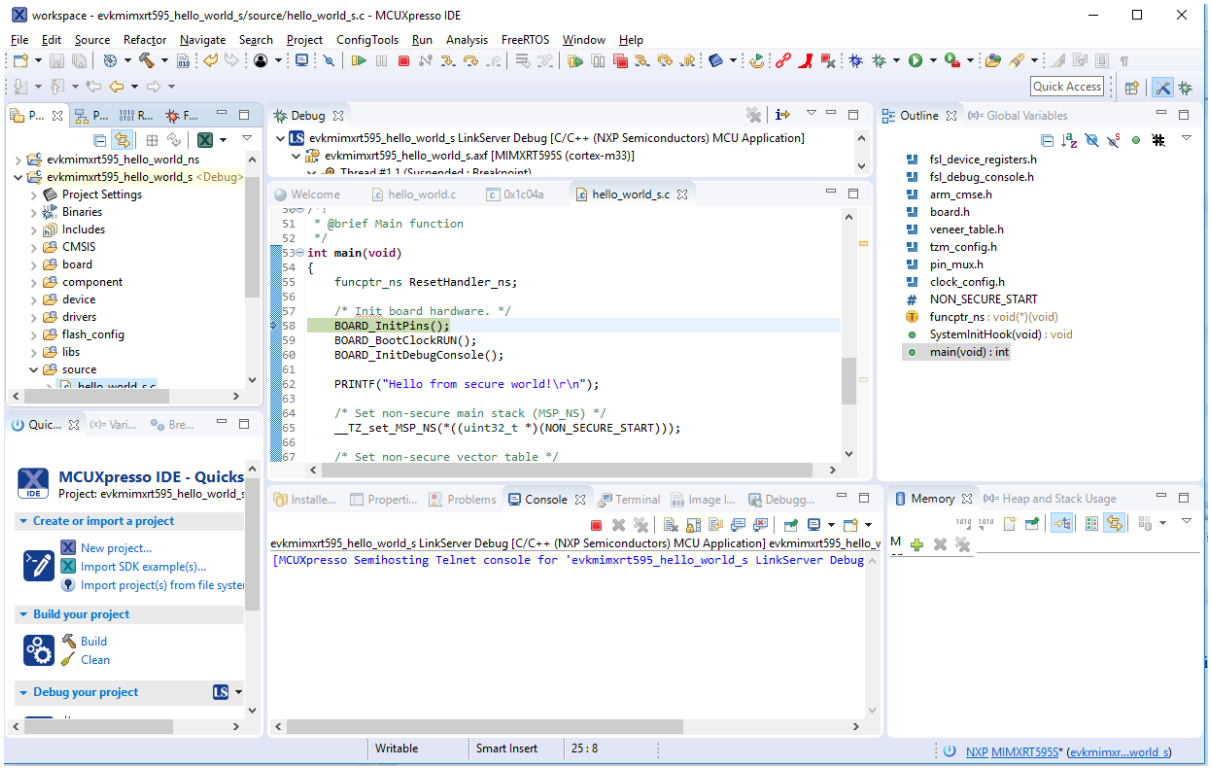
Note: When the **Release** build is requested, it is necessary to change the build configuration of both the secure and non-secure application projects first. To do this, select both projects in the Project Explorer view by clicking to select the first project, then using shift-click or control-click to select the second project. Right click in the Project Explorer view to display the context-sensitive menu and select **Build Configurations** > **Set Active** >**Release**. This is also possible by using the menu item of **Project** > **Build Configuration** >**Set Active** >**Release**. After switching to the **Release** build configuration. Build the application for the secure project first.



Run a TrustZone example application

To download and run the application, perform all steps as described in **Run an example application**. These steps are common for single core, and TrustZone applications, ensuring <board_name>_hello_world_s is selected for debugging.

In the Quickstart Panel, click **Debug** to launch the second debug session.



Now, the TrustZone sessions should be opened. Click **Resume**. The hello_world TrustZone application then starts running, and the secure application starts the non-secure application during runtime.

Run a demo application using IAR This section describes the steps required to build, run, and debug example applications provided in the MCUXpresso SDK.

Note: IAR Embedded Workbench for Arm version 8.32.3 is used in the following example, and the IAR toolchain should correspond to the latest supported version, as described in the *MCUXpresso SDK Release Notes*.

Build an example application

Do the following steps to build the hello_world example application.

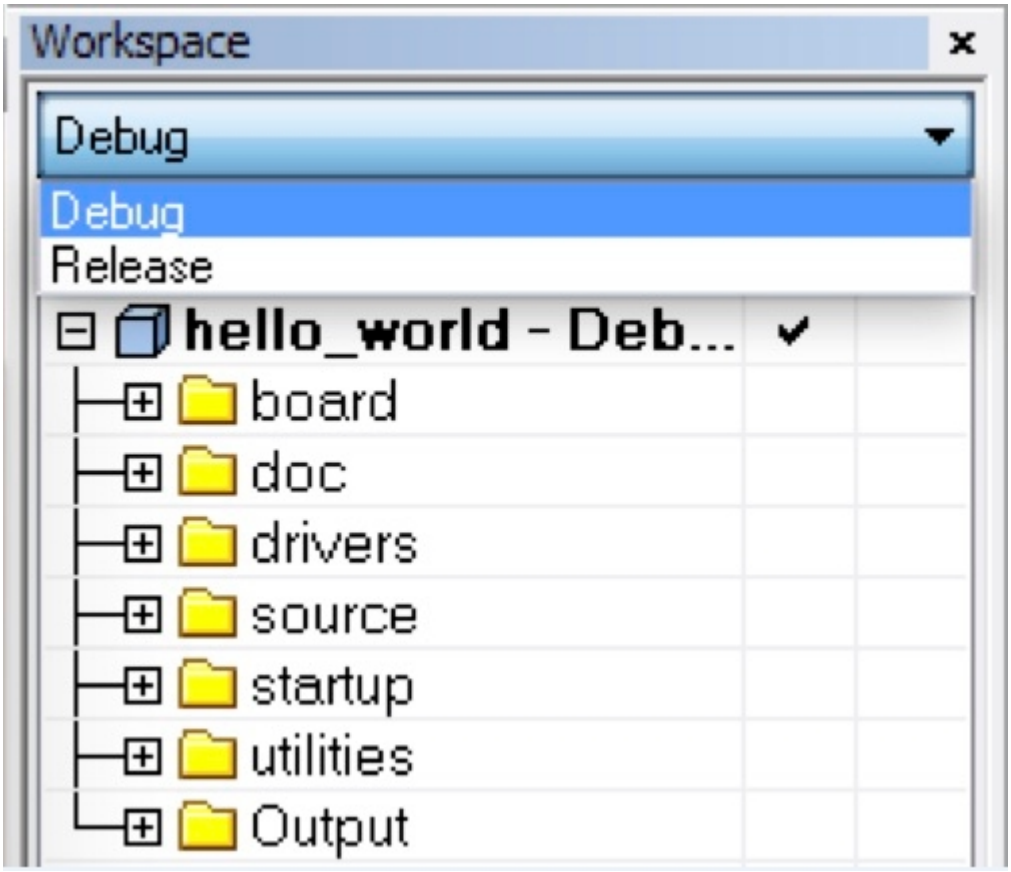
1. Open the desired demo application workspace. Most example application workspace files can be located using the following path:

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

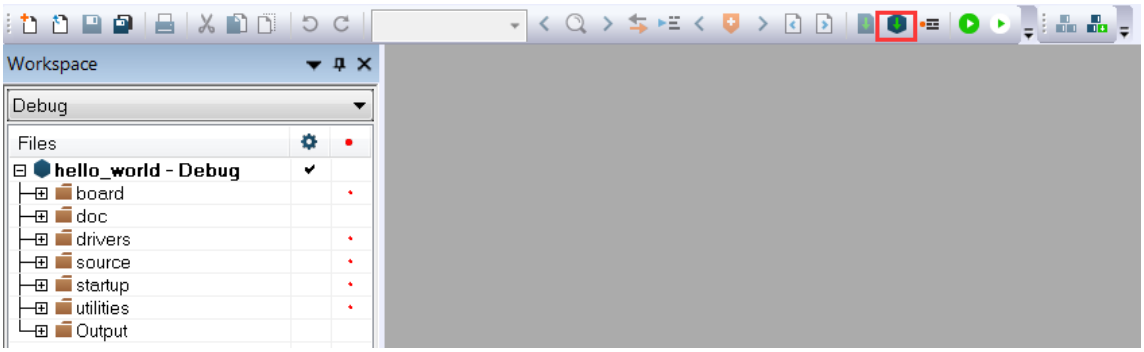
   Other example applications may have additional folders in their path.

2. Select the desired build target from the drop-down menu.

   For this example, select **hello_world – debug**.



3. To build the demo application, click **Make**, highlighted in red in following figure.



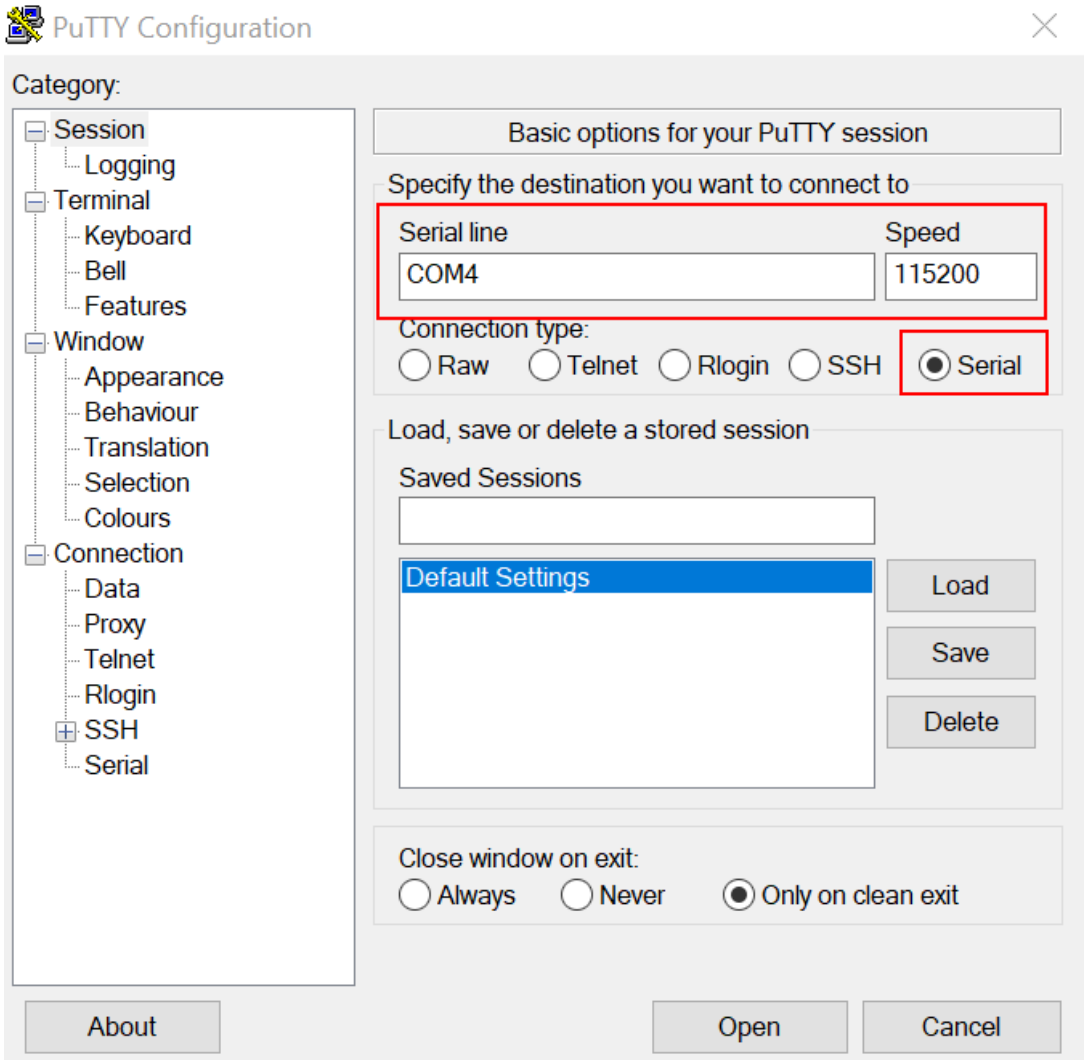
4. The build completes without errors.

Run an example application

To download and run the application, perform these steps:

1. Ensure the host driver for the debugger firmware has been installed. See *On-board debugger*.
2. Connect the development platform to your PC via USB cable.
3. Open the terminal application on the PC, such as PuTTY or TeraTerm, and connect to the debug COM port (to determine the COM port number, see *How to determine COM port*). Configure the terminal with these settings:
    1. 115200 or 9600 baud rate, depending on your board (reference BOARD_DEBUG_UART_BAUDRATE variable in the board.h file)
    2. No parity

3. 8 data bits

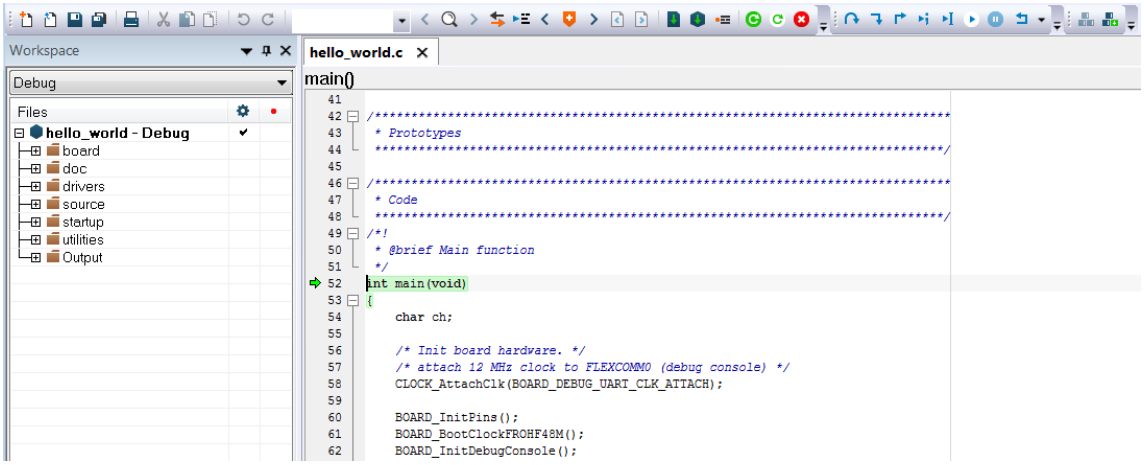


4. 1 stop bit

4. In IAR, click the **Download and Debug** button to download the application to the target.



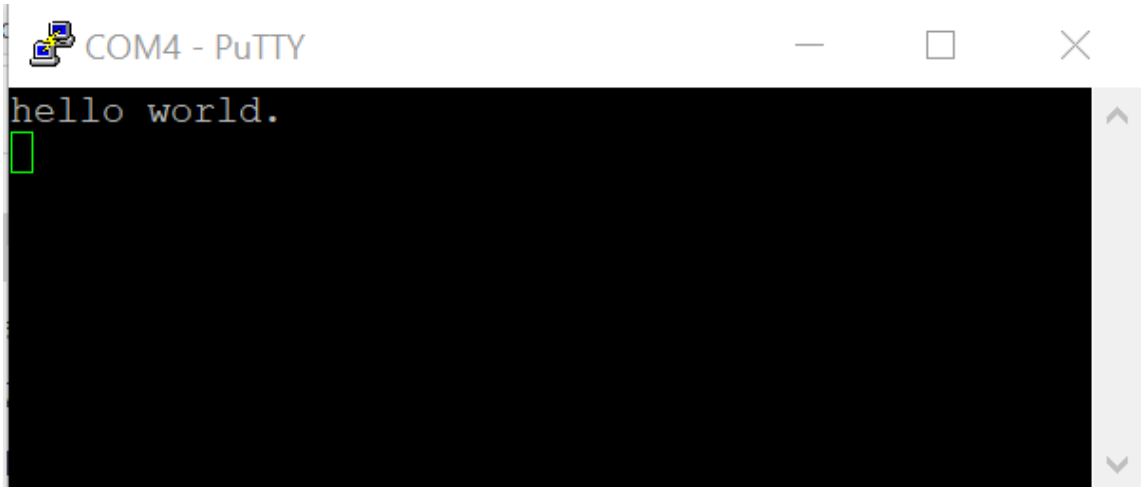
5. The application is then downloaded to the target and automatically runs to the main() function.



6. Run the code by clicking the **Go** button.



7. The hello_world application is now running and a banner is displayed on the terminal. If it does not appear, check your terminal settings and connections.



Build a multicore example application

This section describes the steps to build and run a dual-core application. The demo applications workspace files are located in this folder:

```
<install_dir>/boards/<board_name>/multicore_examples/<application_name>/<core_type>/iar
```

Begin with a simple dual-core version of the Hello World application. The multicore Hello World IAR workspaces are located in this folder:

```
<install_dir>/boards/lpcxpresso54114/multicore_examples/hello_world/cm0plus/iar/hello_world_cm0plus.
↪eww
```

```
<install_dir>/boards/lpcxpresso54114/multicore_examples/hello_world/cm4/iar/hello_world_cm4.eww
```

Build both applications separately by clicking the **Make** button. Build the application for the auxiliary core (cm0plus) first, because the primary core application project (cm4) must know the auxiliary core application binary when running the linker. It is not possible to finish the primary core linker when the auxiliary core application binary is not ready.

Run a multicore example application

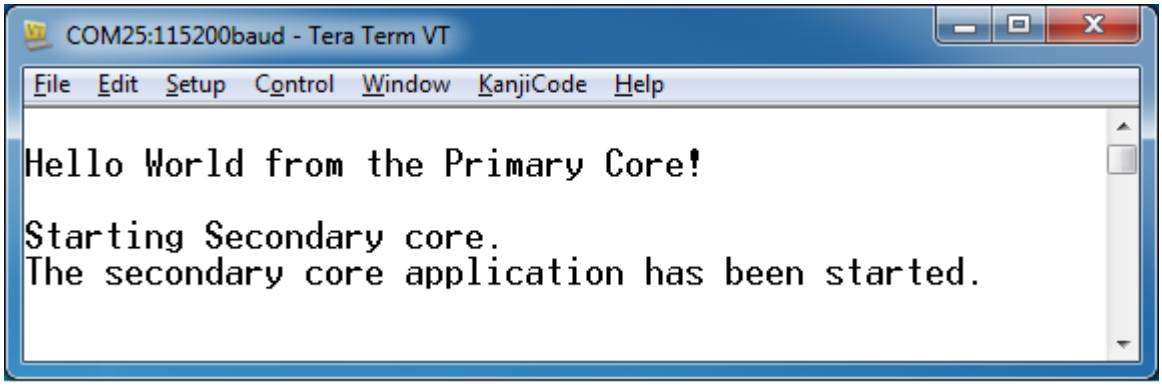
The primary core debugger handles flashing both primary and the auxiliary core applications into the SoC flash memory. To download and run the multicore application, switch to the primary core application project and perform steps 1 – 4 as described in **Run an example application**. These steps are common for both single core and dual-core applications in IAR.

After clicking the “Download and Debug” button, the auxiliary core project is opened in the separate EWARM instance. Both the primary and auxiliary images are loaded into the device flash memory and the primary core application is executed. It stops at the default C language entry point in the *main()*function.

Run both cores by clicking the “Start all cores” button to start the multicore application.



During the primary core code execution, the auxiliary core is released from the reset. The hello_world multicore application is now running and a banner is displayed on the terminal. If this does not appear, check the terminal settings and connections.



An LED controlled by the auxiliary core starts flashing, indicating that the auxiliary core has been released from the reset and is running correctly. When both cores are running, use the "Stop all cores", and "Start all cores" control buttons to stop or run both cores simultaneously.



Build a TrustZone example application

This section describes the particular steps that must be done in order to build and run a TrustZone application. The demo applications workspace files are located in this folder:

```
<install_dir>/boards/<board_name>/trustzone_examples/<application_name>/[<core_type>]/iar/
↪<application_name>_ns/iar
```

```
<install_dir>/boards/<board_name>/trustzone_examples/<application_name>/[<core_type>]/iar/
↪<application_name>_s/iar
```

Begin with a simple TrustZone version of the Hello World application. The TrustZone Hello World IAR workspaces are located in this folder:

```
<install_dir>/boards/<board_name>/trustzone_examples/hello_world/hello_world_ns/iar/hello_world_
↪ns.eww
```

```
<install_dir>/boards/<board_name>/trustzone_examples/hello_world/hello_world_s/iar/hello_world_s.
↪eww
```

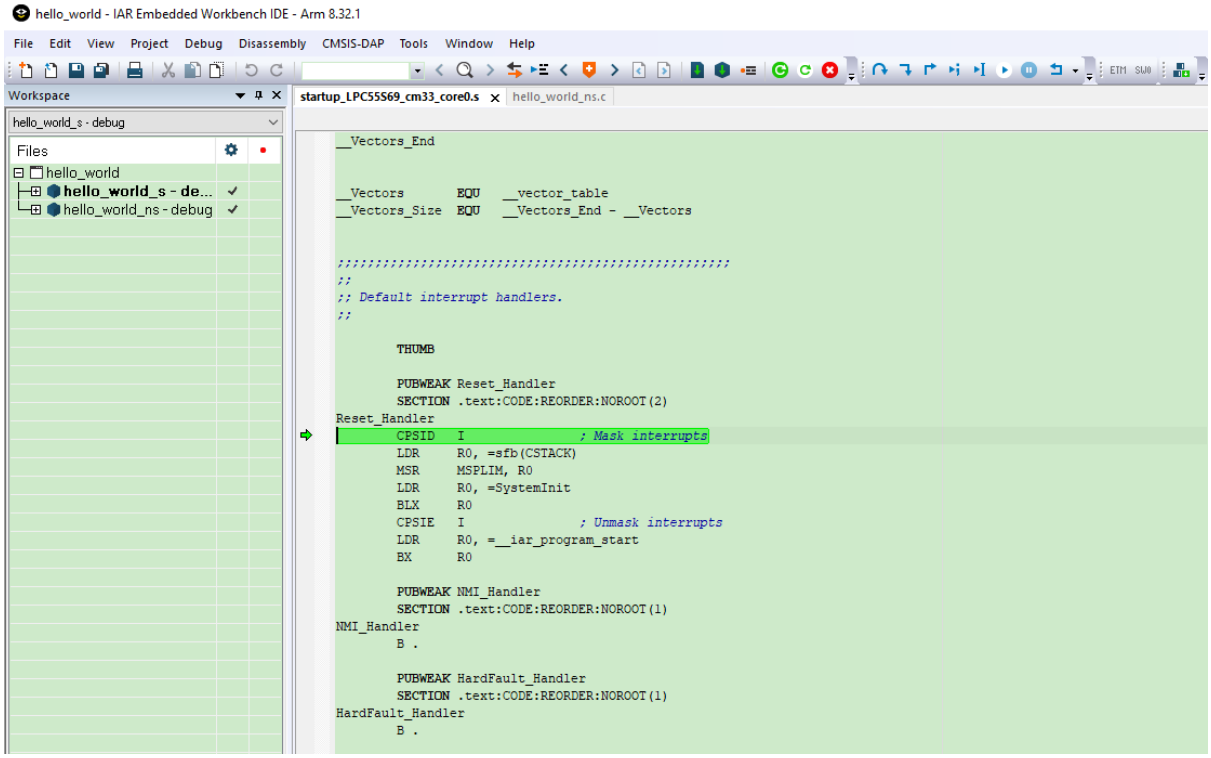
```
<install_dir>/boards/<board_name>/trustzone_examples/hello_world/hello_world_s/iar/hello_world.eww
```

This project hello_world.eww contains both secure and non-secure projects in one workspace and it allows the user to easily transition from one project to another. Build both applications separately by clicking **Make**. It is requested to build the application for the secure project first, because the non-secure project must know the secure project, since the CMSE library is running the linker. It is not possible to finish the non-secure project linker with the secure project since CMSE library is not ready.

Run a TrustZone example application

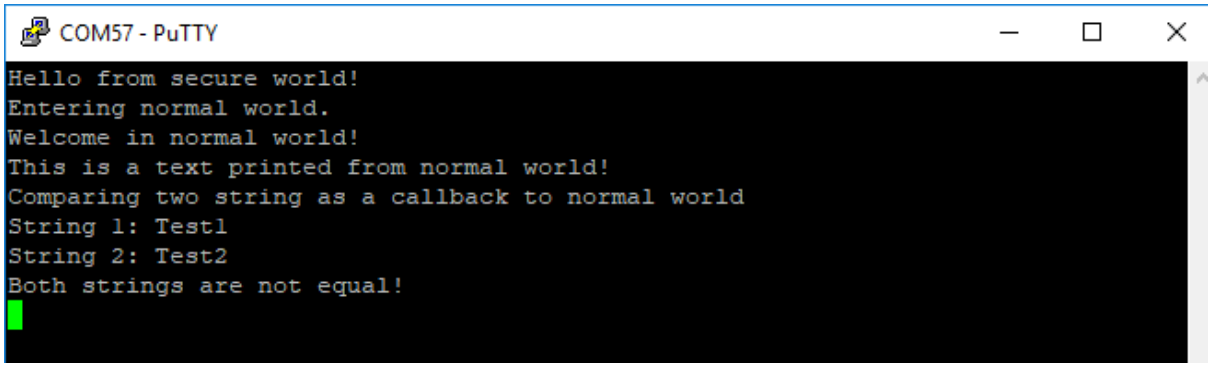
The secure project is configured to download both secure and non-secure output files, so debugging can be fully managed from the secure project. To download and run the TrustZone application, switch to the secure application project and perform steps 1 – 4 as described in **Run an example application**. These steps are common for both single core, and TrustZone applications in IAR. After clicking **Download and Debug**, both the secure and non-secure images are loaded

into the device memory, and the secure application is executed. It stops at the Reset_Handler function.

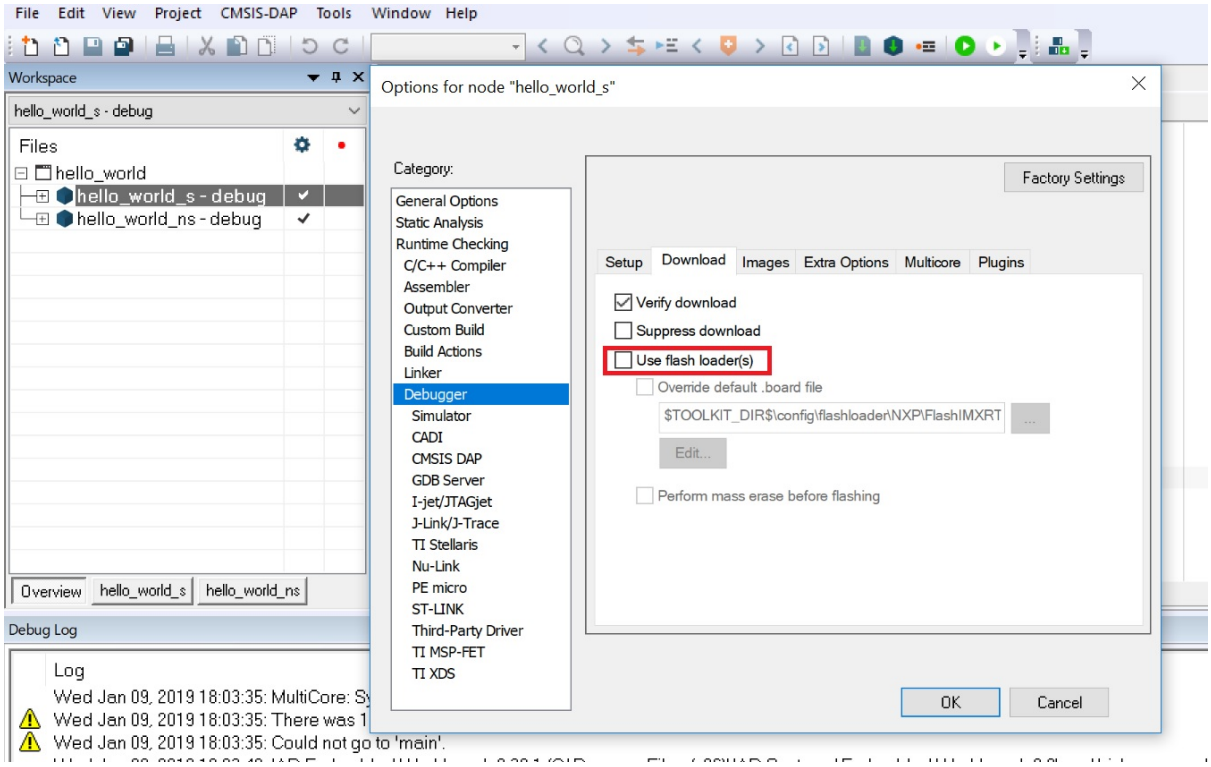


Run the code by clicking **Go** to start the application.

The TrustZone hello_world application is now running and a banner is displayed on the terminal. If this is not true, check your terminal settings and connections.



Note: If the application is running in RAM (debug/release build target), in **Options**>**Debugger** > **Download** tab, disable **Use flash loader(s)**. This can avoid the _ns download issue on i.MXRT500.

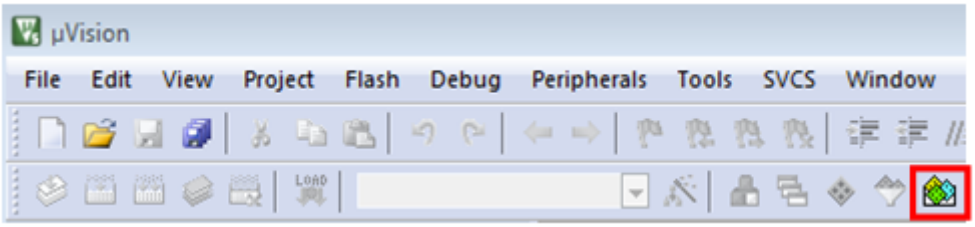


Run a demo using Keil MDK/µVision This section describes the steps required to build, run, and debug example applications provided in the MCUXpresso SDK.

Install CMSIS device pack

After the MDK tools are installed, Cortex Microcontroller Software Interface Standard (CMSIS) device packs must be installed to fully support the device from a debug perspective. These packs include things such as memory map information, register definitions, and flash programming algorithms. Follow these steps to install the appropriate CMSIS pack.

1. Open the MDK IDE, which is called µVision. In the IDE, select the **Pack Installer** icon.



2. After the installation finishes, close the Pack Installer window and return to the µVision IDE.

Build an example application

1. Open the desired example application workspace in:

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

   The workspace file is named as <demo_name>.uvmpw. For this specific example, the actual path is:

2. To build the demo project, select **Rebuild**, highlighted in red.

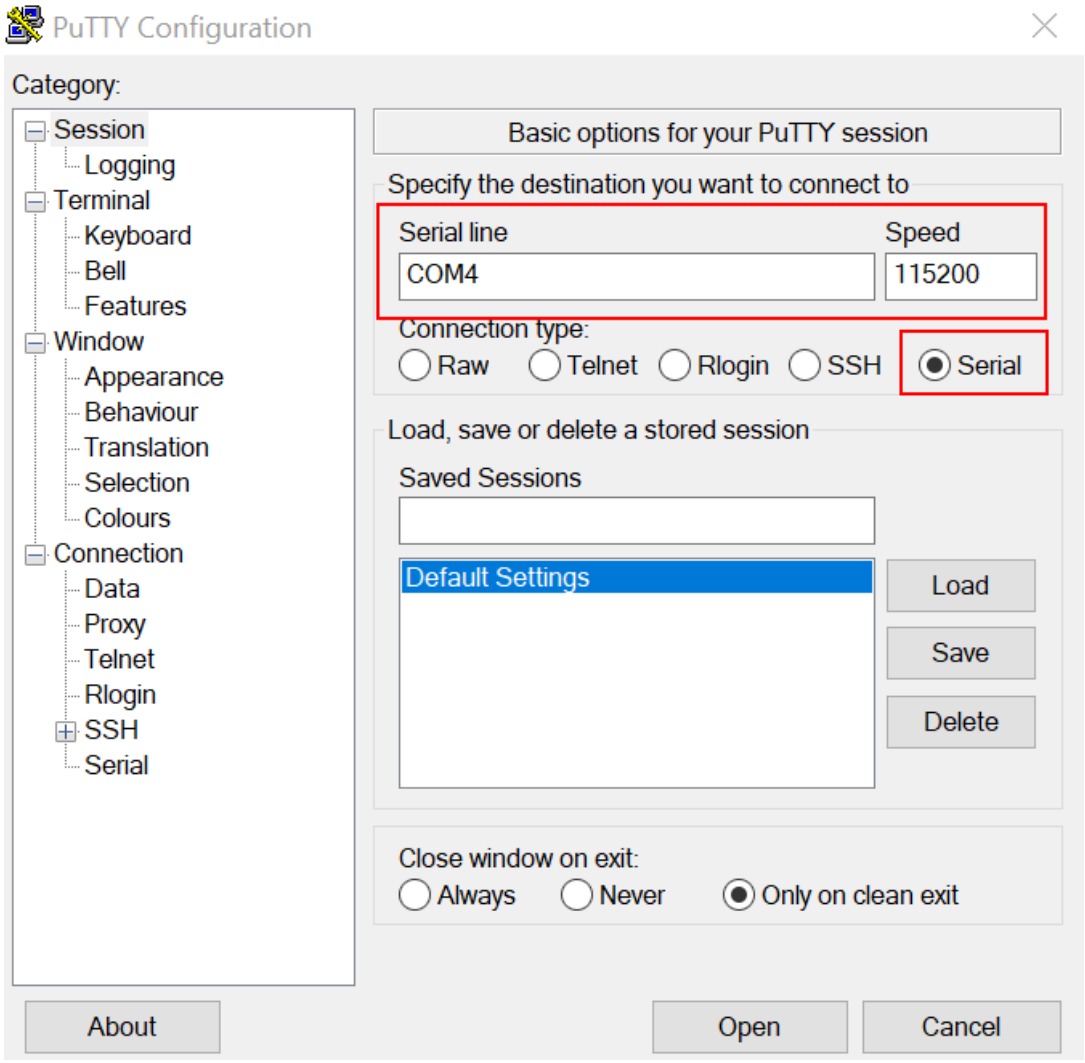


3. The build completes without errors.

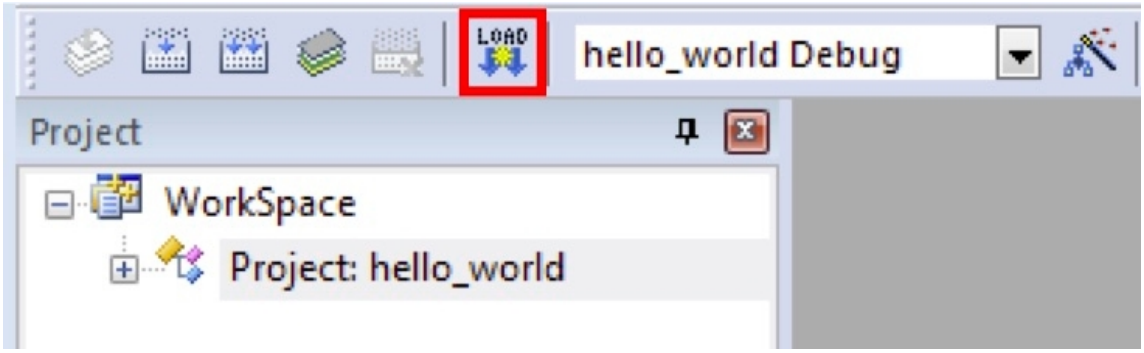
Run an example application

To download and run the application, perform these steps:

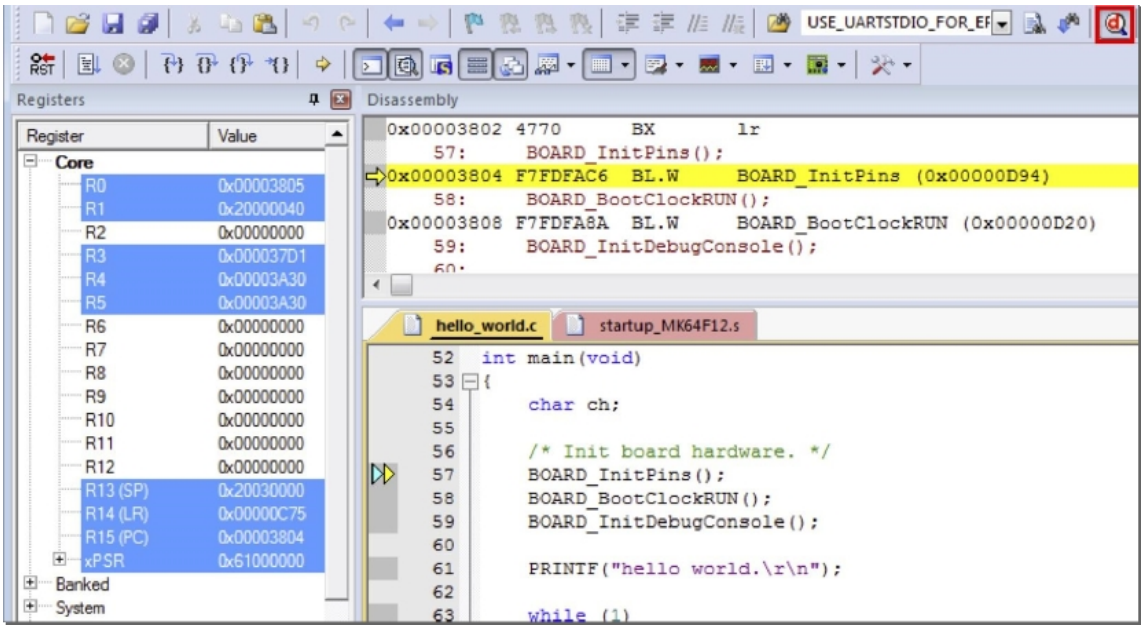
1. Ensure the host driver for the debugger firmware has been installed. See *On-board debugger*.
2. Connect the development platform to your PC via USB cable using USB connector.
3. Open the terminal application on the PC, such as PuTTY or TeraTerm and connect to the debug serial port number (to determine the COM port number, see *How to determine COM port*. Configure the terminal with these settings:
    1. 115200 or 9600 baud rate, depending on your board (reference BOARD_DEBUG_UART_BAUDRATE variable in the board.h file)
    2. No parity
    3. 8 data bits
    4. 1 stop bit



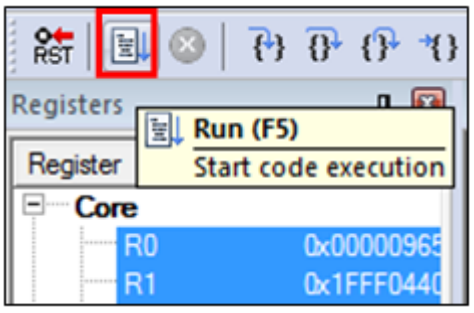
4. In µVision, after the application is built, click the **Download** button to download the application to the target.



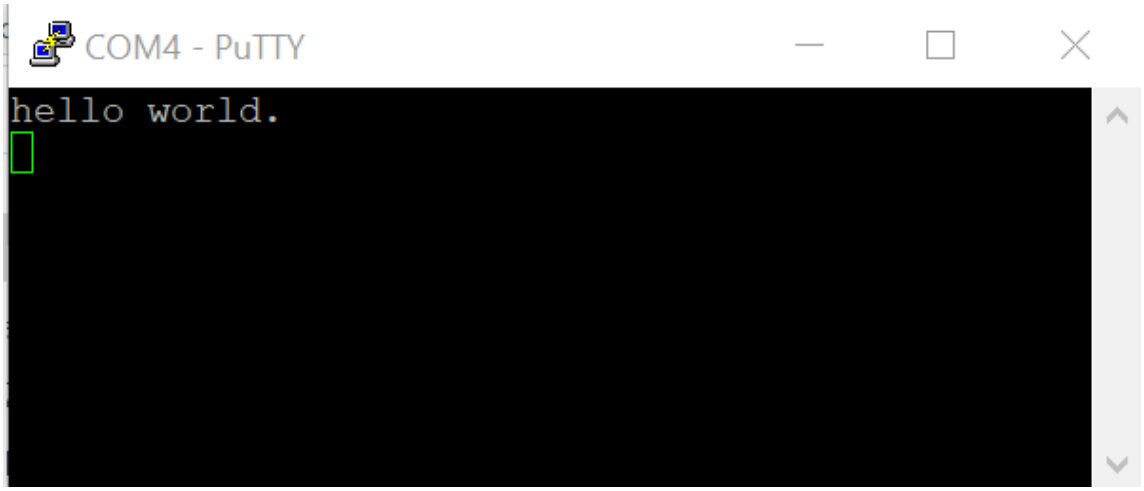
5. After clicking the **Download** button, the application downloads to the target and is running. To debug the application, click the **Start/Stop Debug Session** button, highlighted in red.



6. Run the code by clicking the **Run** button to start the application.



The hello_world application is now running and a banner is displayed on the terminal. If this does not appear, check your terminal settings and connections.



Build a multicore example application

This section describes the steps to build and run a dual-core application. The demo applications workspace files are located in this folder:

```
<install_dir>/boards/<board_name>/multicore_examples/<application_name>/<core_type>/mdk
```

Begin with a simple dual-core version of the Hello World application. The multicore Hello World Keil MSDK/µVision workspaces are located in this folder:

```
<install_dir>/boards/lpcxpresso54114/multicore_examples/hello_world/cm0plus/mdk/hello_world_
↪cm0plus.uvmpw
```

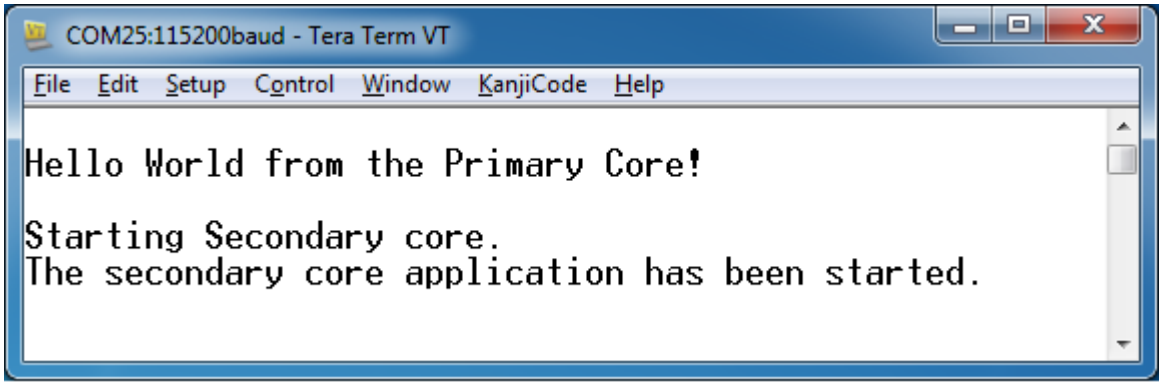
```
<install_dir>/boards/lpcxpresso54114/multicore_examples/hello_world/cm4/mdk/hello_world_cm4.uvmpw
```

Build both applications separately by clicking the **Rebuild** button. Build the application for the auxiliary core (cm0plus) first because the primary core application project (cm4) must know the auxiliary core application binary when running the linker. It is not possible to finish the primary core linker when the auxiliary core application binary is not ready.

Run a multicore example application

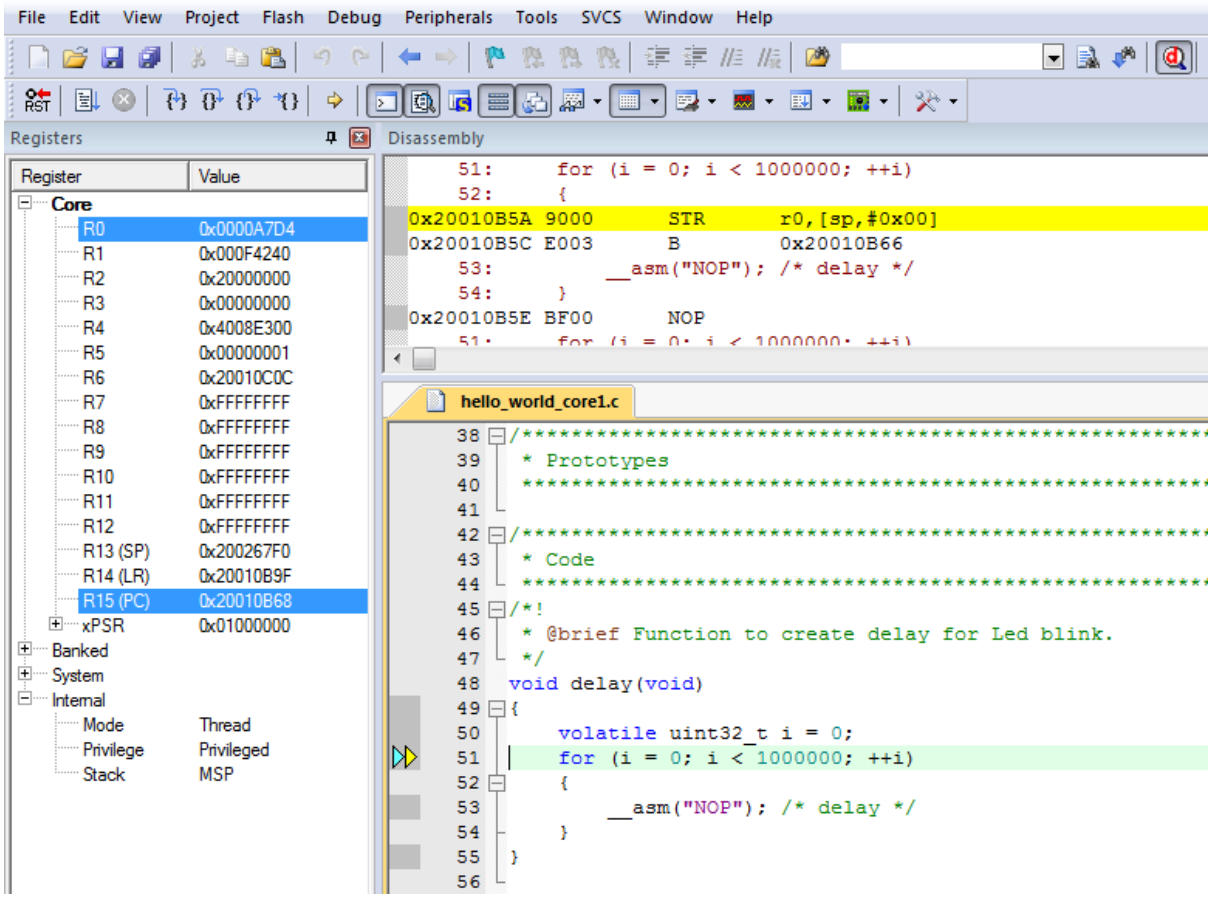
The primary core debugger flashes both the primary and the auxiliary core applications into the SoC flash memory. To download and run the multicore application, switch to the primary core application project and perform steps 1 – 5 as described in **Run an example application**. These steps are common for both single-core and dual-core applications in µVision.

Both the primary and the auxiliary image is loaded into the device flash memory. After clicking the “Run” button, the primary core application is executed. During the primary core code execution, the auxiliary core is released from the reset. The hello_world multicore application is now running and a banner is displayed on the terminal. If this does not appear, check your terminal settings and connections.



An LED controlled by the auxiliary core starts flashing indicating that the auxiliary core has been released from the reset and is running correctly.

Attach the running application of the auxiliary core by opening the auxiliary core project in the second µVision instance and clicking the "Start/Stop Debug Session" button. After this, the second debug session is opened and the auxiliary core application can be debugged.



Arm describes multicore debugging using the NXP LPC54114 Cortex-M4/M0+ dual-core processor and Keil uVision IDE in Application Note 318 at www.keil.com/appnotes/docs/apnt_318.asp. The associated video can be found here.

Build a TrustZone example application

This section describes the particular steps that must be done in order to build and run a TrustZone application. The demo applications workspace files are located in this folder:

```
<install_dir>/boards/<board_name>/trustzone_examples/<application_name>/<application_name>_ns/
↪mdk
```

```
<install_dir>/boards/<board_name>/trustzone_examples/<application_name>/<application_name>_s/
↪mdk
```

Begin with a simple TrustZone version of the Hello World application. The TrustZone Hello World Keil MSDK/µVision workspaces are located in this folder:

```
<install_dir>/boards/<board_name>/trustzone_examples/hello_world/hello_world_ns/mdk/hello_world_
↪ns.uvmpw
```

```
<install_dir>/boards/<board_name>/trustzone_examples/hello_world/hello_world_s/mdk/hello_world_s.
↪uvmpw
```

```
<install_dir>/boards/<board_name>/trustzone_examples/hello_world/hello_world_s/mdk/hello_world.
↪uvmpw
```

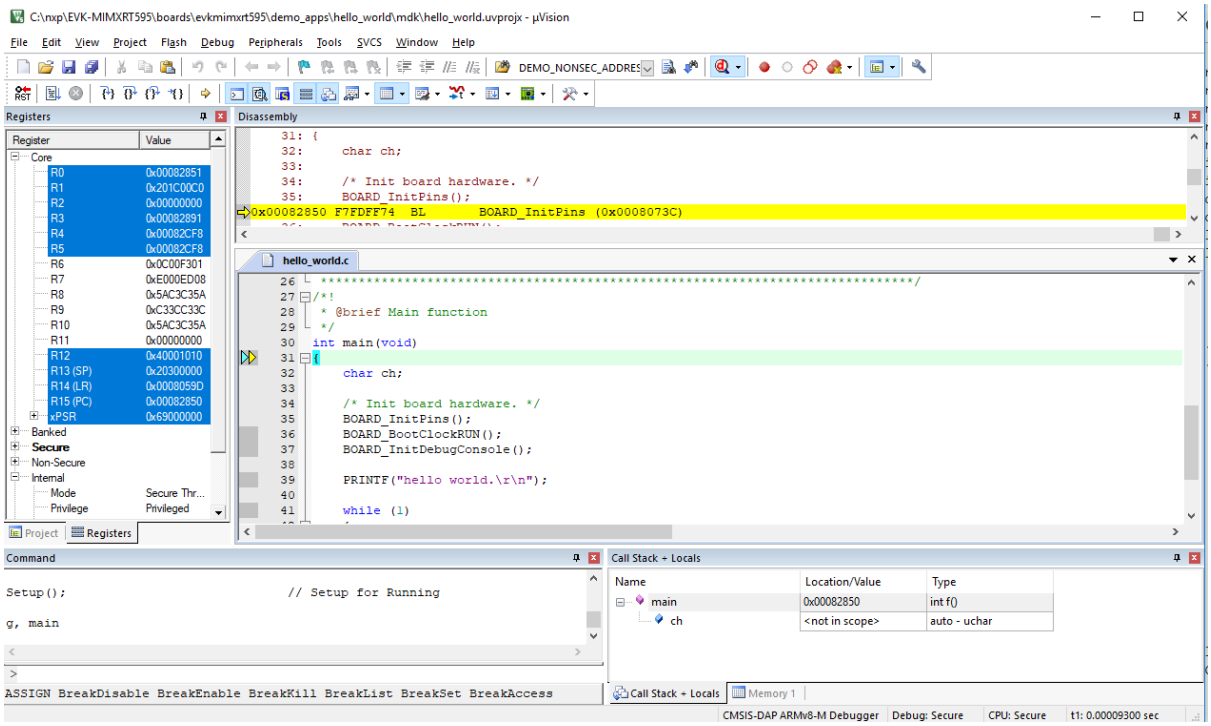
This project hello_world.uvmpw contains both secure and non-secure projects in one workspace and it allows the user to easily transition from one project to another.

Build both applications separately by clicking **Rebuild**. It is requested to build the application for the secure project first, because the non-secure project must know the secure project since CMSE library is running the linker. It is not possible to finish the non-secure project linker with the secure project because CMSE library is not ready.

Run a TrustZone example application

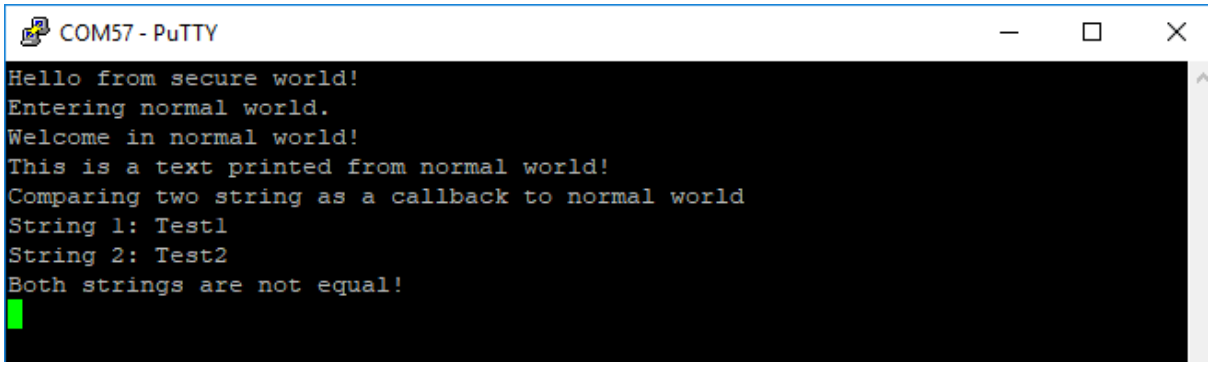
The secure project is configured to download both secure and non-secure output files so debugging can be fully managed from the secure project.

To download and run the TrustZone application, switch to the secure application project and perform steps as described in **Run an example application**. These steps are common for single core, dual-core, and TrustZone applications in µVision. After clicking **Download and Debug**, both the secure and non-secure images are loaded into the device flash memory, and the secure application is executed. It stops at the main() function.



Run the code by clicking **Run** to start the application.

The hello_world application is now running and a banner is displayed on the terminal. If not, check your terminal settings and connections.



Run a demo using ARMGCC / VSCODE This section describes the steps to run an example application from the SDK archive using the ARMGCC / VSCODE toolchain.

Refer to the *running a demo using MCUXpresso VSC* section for detailed instructions on setting up and configuring your project in Visual Studio Code.

Refer to the *CLI* section for detailed instructions on building and running your project from the command line.

MCUXpresso Config Tools MCUXpresso Config Tools can help configure the processor and generate initialization code for the on chip peripherals. The tools are able to modify any existing example project, or create a new configuration for the selected board or processor. The generated code is designed to be used with MCUXpresso SDK version 24.12.00 or later.

Following table describes the tools included in the MCUXpresso Config Tools.

Config Tool	Description	Image
Pins tool	For configuration of pin routing and pin electrical properties.	
Clock tool	For system clock configuration	
Peripherals tools	For configuration of other peripherals	
TEE tool	Configures access policies for memory area and peripherals helping to protect and isolate sensitive parts of the application.	
Device Configuration tool	Configures Device Configuration Data (DCD) contained in the program image that the Boot ROM code interprets to set up various on-chip peripherals prior to the program launch.	

MCUXpresso Config Tools can be accessed in the following products:

- **Integrated** in the MCUXpresso IDE. Config tools are integrated with both compiler and debugger which makes it the easiest way to begin the development.
- **Standalone version** available for download from www.nxp.com/mcuxpresso. Recommended for customers using IAR Embedded Workbench, Keil MDK µVision, or Arm GCC.

- **Online version** available on mcuxpresso.nxp.com. Recommended doing a quick evaluation of the processor or use the tool without installation.

Each version of the product contains a specific *Quick Start Guide* document MCUXpresso IDE Config Tools installation folder that can help start your work.

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

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

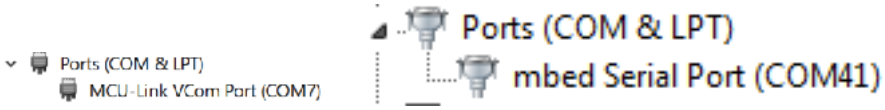
```
$ dmesg | grep "ttyUSB"
  [503175.307873] usb 3-12: cp210x converter now attached to ttyUSB0
  [503175.309372] usb 3-12: cp210x converter now attached to ttyUSB1
```

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

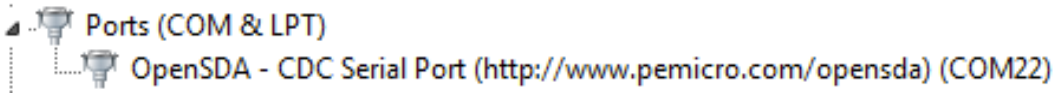
2. **Windows**: To determine the COM port open Device Manager in the Windows operating system. Click the **Start** menu and type **Device Manager** in the search bar.

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

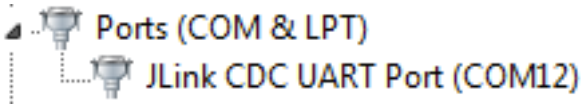
   1. **CMSIS-DAP/mbed/DAPLink** interface:

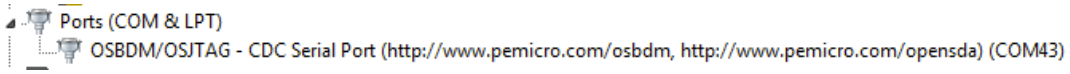
   2. **P&E Micro**:

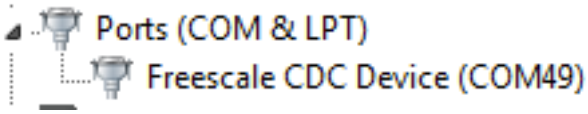
   3. **J-Link**:

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

   5. **MRB-KW01**:

On-board Debugger This section describes the on-board debuggers used on NXP development boards.

On-board debugger MCU-Link

MCU-Link is a powerful and cost effective debug probe that can be used seamlessly with MCUXpresso IDE, and is also compatible with 3rd party IDEs that support CMSIS-DAP protocol. MCU-Link also includes a USB to UART bridge feature (VCOM) that can be used to provide a serial connection between the target MCU and a host computer. MCU-Link features a high-speed USB interface for high performance debug. MCU-Link is compatible with Windows, MacOS and Linux. A free utility from NXP provides an easy way to install firmware updates.

On-board MCU-Link debugger supports CMSIS-DAP and J-Link firmware. See the table in *Default debug interfaces* to determine the default debug interface that comes loaded on your specific hardware platform.

The corresponding host driver must be installed before debugging.

- For boards with CMSIS-DAP firmware, visit developer.mbed.org/handbook/Windows-serial-configuration and follow the instructions to install the Windows operating system serial driver. If running on Linux OS, this step is not required.
- If using J-Link with either a standalone debug pod or MCU-Link, install the J-Link software (drivers and utilities) from www.segger.com/jlink-software.html.

Updating MCU-Link firmware

This firmware in this debug interface may be updated using the host computer utility called MCU-Link. This typically used when switching between the default debugger protocol (CMSIS-DAP) to SEGGER J-Link, or for updating this firmware with new releases of these. This section contains the steps to reprogram the debug probe firmware.

Note: If MCUXpresso IDE is used and the jumper making DFUlink is installed on the board (JP5 on some boards, but consult the board user manual or schematic for specific jumper number), MCU-Link debug probe boots to DFU mode, and MCUXpresso IDE automatically downloads the CMSIS-DAP firmware to the probe before flash memory programming (after clicking **Debug**). Using DFU mode ensures that most up-to-date/compatible firmware is used with MCUXpresso IDE.

NXP provides the MCU-Link utility, which is the recommended tool for programming the latest versions of CMSIS-DAP and J-Link firmware onto MCU-Link or NXP boards. The utility can be downloaded from MCU-Link.

These steps show how to update the debugger firmware on your board for Windows operating system.

1. Install the MCU-Link utility.
2. Unplug the board's USB cable.
3. Make the DFU link (install the jumper labeled DFUlink).
4. Connect the probe to the host via USB (use Link USB connector).
5. Open a command shell and call the appropriate script located in the MCU-Link installation directory (<MCU-Link install dir>).
    1. To program CMSIS-DAP debug firmware: <MCU-Link install dir>/scripts/program_CMSIS
    2. To program J-Link debug firmware: <MCU-Link install dir>/scripts/program_JLINK
6. Remove DFU link (remove the jumper installed in Step 3).
7. Repower the board by removing the USB cable and plugging it in again.

On-board debugger LPC-Link

LPC-Link 2 is an extensible debug probe that can be used seamlessly with MCUXpresso IDE, and is also compatible with 3rd party IDEs that support CMSIS-DAP protocol. MCU-Link also includes a USB to UART bridge feature (VCOM) that can be used to provide a serial connection between

the target MCU and a host computer. LPC-Link 2 is compatible with Windows, MacOS and Linux. A free utility from NXP provides an easy way to install firmware updates.

On-board LPC-Link 2 debugger supports CMSIS-DAP and J-Link firmware. See the table in *Default debug interfaces* to determine the default debug interface that comes loaded on your specific hardware platform.

The corresponding host driver must be installed before debugging.

- For boards with CMSIS-DAP firmware, visit developer.mbed.org/handbook/Windows-serial-configuration and follow the instructions to install the Windows operating system serial driver. If running on Linux OS, this step is not required.
- If using J-Link with either a standalone debug pod or MCU-Link, install the J-Link software (drivers and utilities) from www.segger.com/jlink-software.html.

Updating LPC-Link firmware

The LPCXpresso hardware platform comes with a CMSIS-DAP-compatible debug interface (known as LPC-Link2). This firmware in this debug interface may be updated using the host computer utility called LPCScrypt. This typically used when switching between the default debugger protocol (CMSIS-DAP) to SEGGER J-Link, or for updating this firmware with new releases of these. This section contains the steps to reprogram the debug probe firmware.

Note: If MCUXpresso IDE is used and the jumper making DFUlink is installed on the board (JP5 on some boards, but consult the board user manual or schematic for specific jumper number), LPC-Link2 debug probe boots to DFU mode, and MCUXpresso IDE automatically downloads the CMSIS-DAP firmware to the probe before flash memory programming (after clicking **Debug**). Using DFU mode ensures that most up-to-date/compatible firmware is used with MCUXpresso IDE.

NXP provides the LPCScrypt utility, which is the recommended tool for programming the latest versions of CMSIS-DAP and J-Link firmware onto LPC-Link2 or LPCXpresso boards. The utility can be downloaded from LPCScrypt.

These steps show how to update the debugger firmware on your board for Windows operating system. For Linux OS, follow the instructions described in LPCScrypt user guide (LPCScrypt, select **LPCScrypt**, and then the documentation tab).

1. Install the LPCScript utility.
2. Unplug the board's USB cable.
3. Make the DFU link (install the jumper labeled DFUlink).
4. Connect the probe to the host via USB (use Link USB connector).
5. Open a command shell and call the appropriate script located in the LPCScrypt installation directory (<LPCScrypt install dir>).
    1. To program CMSIS-DAP debug firmware: <LPCScrypt install dir>/scripts/program_CMSIS
    2. To program J-Link debug firmware: <LPCScrypt install dir>/scripts/program_JLINK
6. Remove DFU link (remove the jumper installed in Step 3).
7. Repower the board by removing the USB cable and plugging it in again.

On-board debugger OpenSDA

OpenSDA/OpenSDAv2 is a serial and debug adapter that is built into several NXP evaluation boards. It provides a bridge between your computer (or other USB host) and the embedded target processor, which can be used for debugging, flash programming, and serial communication, all over a simple USB cable.

The difference is the firmware implementation: OpenSDA: Programmed with the proprietary P&E Micro developed bootloader. P&E Micro is the default debug interface app. OpenSDAv2: Programmed with the open-sourced CMSIS-DAP/mbed bootloader. CMSIS-DAP is the default debug interface app.

See the table in *Default debug interfaces* to determine the default debug interface that comes loaded on your specific hardware platform.

The corresponding host driver must be installed before debugging.

- For boards with CMSIS-DAP firmware, visit developer.mbed.org/handbook/Windows-serial-configuration and follow the instructions to install the Windows operating system serial driver. If running on Linux OS, this step is not required.
- For boards with a P&E Micro interface, see PE micro to download and install the P&E Micro Hardware Interface Drivers package.

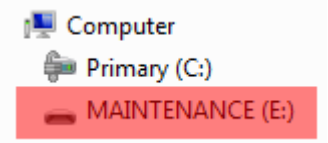
Updating OpenSDA firmware

Any NXP hardware platform that comes with an OpenSDA-compatible debug interface has the ability to update the OpenSDA firmware. This typically means to switch from the default application (either CMSIS-DAP or P&E Micro) to a SEGGER J-Link. This section contains the steps to switch the OpenSDA firmware to a J-Link interface. However, the steps can be applied to restoring the original image also. For reference, OpenSDA firmware files can be found at the links below:

- J-Link: Download appropriate image from www.segger.com/opensda.html. Choose the appropriate J-Link binary based on the table in *Default debug interfaces*. Any OpenSDA v1.0 interface should use the standard OpenSDA download (in other words, the one with no version). For OpenSDA 2.0 or 2.1, select the corresponding binary.
- CMSIS-DAP: CMSIS-DAP OpenSDA firmware is available at www.nxp.com/opensda.
- P&E Micro: Downloading P&E Micro OpenSDA firmware images requires registration with P&E Micro (www.pemicro.com).

Perform the following steps to update the OpenSDA firmware on your board for Windows and Linux OS users:

1. Unplug the board's USB cable.
2. Press the **Reset** button on the board. While still holding the button, plug the USB cable back into the board.
3. When the board re-enumerates, it shows up as a disk drive called **MAINTENANCE**.



4. Drag and drop the new firmware image onto the MAINTENANCE drive.

   Note: If for any reason the firmware update fails, the board can always reenter maintenance mode by holding down **Reset** button and power cycling.

These steps show how to update the OpenSDA firmware on your board for Mac OS users.

1. Unplug the board's USB cable.
2. Press the **Reset** button of the board. While still holding the button, plug the USB cable back into the board.
3. For boards with OpenSDA v2.0 or v2.1, it shows up as a disk drive called **BOOTLOADER** in **Finder**. Boards with OpenSDA v1.0 may or may not show up depending on the bootloader version. If you see the drive in **Finder**, proceed to the next step. If you do not see the drive

in Finder, use a PC with Windows OS 7 or an earlier version to either update the OpenSDA firmware, or update the OpenSDA bootloader to version 1.11 or later. The bootloader update instructions and image can be obtained from P&E Microcomputer website.

4. For OpenSDA v2.1 and OpenSDA v1.0 (with bootloader 1.11 or later) users, drag the new firmware image onto the BOOTLOADER drive in **Finder**.
5. For OpenSDA v2.0 users, type these commands in a Terminal window:

```
> sudo mount -u -w -o sync /Volumes/BOOTLOADER
> cp -X  <path to update file> /Volumes/BOOTLOADER
```

Note: If for any reason the firmware update fails, the board can always reenter bootloader mode by holding down the **Reset** button and power cycling.

On-board debugger Multilink

An on-board Multilink debug circuit provides a JTAG interface and a power supply input through a single micro-USB connector. It is a hardware interface that allows PC software to debug and program a target processor through its debug port.

The host driver must be installed before debugging.

- See PE micro to download and install the P&E Micro Hardware Interface Drivers package.

On-board debugger OSJTAG

An on-board OSJTAG debug circuit provides a JTAG interface and a power supply input through a single micro-USB connector. It is a hardware interface that allows PC software to debug and program a target processor through its debug port.

The host driver must be installed before debugging.

- See PE micro to download and install the P&E Micro Hardware Interface Drivers package.

Default debug interfaces The MCUXpresso SDK supports various hardware platforms that come loaded with various factory programmed debug interface configurations. The following table lists the hardware platforms supported by the MCUXpresso SDK, their default debug firmware, and any version information that helps differentiate a specific interface configuration.

Hardware platform	Default debugger firmware	On-board debugger probe
EVK-MCIMX7ULP	N/A	N/A
EVK-MIMX8MM	N/A	N/A
EVK-MIMX8MN	N/A	N/A
EVK-MIMX8MNDDR3L	N/A	N/A
EVK-MIMX8MP	N/A	N/A
EVK-MIMX8MQ	N/A	N/A
EVK-MIMX8ULP	N/A	N/A
EVK-MIMXRT1010	CMSIS-DAP	LPC-Link2
EVK-MIMXRT1015	CMSIS-DAP	LPC-Link2
EVK-MIMXRT1020	CMSIS-DAP	LPC-Link2
EVK-MIMXRT1064	CMSIS-DAP	LPC-Link2
EVK-MIMXRT595	CMSIS-DAP	LPC-Link2
EVK-MIMXRT685	CMSIS-DAP	LPC-Link2
EVK9-MIMX8ULP	N/A	N/A
EVKB-IMXRT1050	CMSIS-DAP	LPC-Link2
FRDM-K22F	CMSIS-DAP	OpenSDA v2
FRDM-K32L2A4S	CMSIS-DAP	OpenSDA v2
FRDM-K32L2B	CMSIS-DAP	OpenSDA v2

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Table 1 – continued from previous page

Hardware platform	Default debugger firmware	On-board debugger probe
FRDM-K32L3A6	CMSIS-DAP	OpenSDA v2
FRDM-KE02Z40M	P&E Micro	OpenSDA v1
FRDM-KE15Z	CMSIS-DAP	OpenSDA v2
FRDM-KE16Z	CMSIS-DAP	OpenSDA v2
FRDM-KE17Z	CMSIS-DAP	OpenSDA v2
FRDM-KE17Z512	CMSIS-DAP	MCU-Link
FRDM-MCXA153	CMSIS-DAP	MCU-Link
FRDM-MCXA156	CMSIS-DAP	MCU-Link
FRDM-MCXA174	CMSIS-DAP	MCU-Link
FRDM-MCXA266	CMSIS-DAP	MCU-Link
FRDM-MCXA344	CMSIS-DAP	MCU-Link
FRDM-MCXA346	CMSIS-DAP	MCU-Link
FRDM-MCXA366	CMSIS-DAP	MCU-Link
FRDM-MCXA577	CMSIS-DAP	MCU-Link
FRDM-MCXC041	CMSIS-DAP	MCU-Link
FRDM-MCXC162	CMSIS-DAP	MCU-Link
FRDM-MCXC242	CMSIS-DAP	MCU-Link
FRDM-MCXC353	CMSIS-DAP	MCU-Link
FRDM-MCXC444	CMSIS-DAP	MCU-Link
FRDM-MCXE247	CMSIS-DAP	MCU-Link
FRDM-MCXE31B	CMSIS-DAP	MCU-Link
FRDM-MCXN236	CMSIS-DAP	MCU-Link
FRDM-MCXN947	CMSIS-DAP	MCU-Link
FRDM-MCXN947T	CMSIS-DAP	MCU-Link
FRDM-MCXW23	CMSIS-DAP	MCU-Link
FRDM-MCXW71	CMSIS-DAP	MCU-Link
FRDM-MCXW72	CMSIS-DAP	MCU-Link
FRDM-RW612	CMSIS-DAP	MCU-Link
FRDM-KW43	CMSIS-DAP	MCU-Link
FRDM-MCXW70	CMSIS-DAP	MCU-Link
KW43-LOC	CMSIS-DAP	MCU-Link
MCXW70-LOC	CMSIS-DAP	MCU-Link
IMX943-EVK	N/A	N/A
IMX95LP4XEVK-15	N/A	N/A
IMX95LPD5EVK-19	N/A	N/A
IMX95VERDINEVK	N/A	N/A
KW45B41Z-EVK	CMSIS-DAP	MCU-Link
KW45B41Z-LOC	CMSIS-DAP	MCU-Link
KW47-EVK	CMSIS-DAP	MCU-Link
KW47-LOC	CMSIS-DAP	MCU-Link
LPC845BREAKOUT	CMSIS-DAP	LPC-Link2
LPCXpresso51U68	CMSIS-DAP	LPC-Link2
LPCXpresso54628	CMSIS-DAP	LPC-Link2
LPCXpresso54S018	CMSIS-DAP	LPC-Link2
LPCXpresso54S018M	CMSIS-DAP	LPC-Link2
LPCXpresso55S06	CMSIS-DAP	LPC-Link2
LPCXpresso55S16	CMSIS-DAP	LPC-Link2
LPCXpresso55S28	CMSIS-DAP	LPC-Link2
LPCXpresso55S36	CMSIS-DAP	MCU-Link
LPCXpresso55S69	CMSIS-DAP	LPC-Link2
LPCXpresso802	CMSIS-DAP	LPC-Link2
LPCXpresso804	CMSIS-DAP	LPC-Link2
LPCXpresso824MAX	CMSIS-DAP	LPC-Link2
LPCXpresso845MAX	CMSIS-DAP	LPC-Link2
LPCXpresso860MAX	CMSIS-DAP	LPC-Link2

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Table 1 – continued from previous page

Hardware platform	Default debugger firmware	On-board debugger probe
MC56F80000-EVK	P&E Micro	Multilink
MC56F81000-EVK	P&E Micro	Multilink
MC56F83000-EVK	P&E Micro	OSJTAG
MCIMX93-EVK	N/A	N/A
MCIMX93-QSB	N/A	N/A
MCIMX93AUTO-EVK	N/A	N/A
MCX-N5XX-EVK	CMSIS-DAP	MCU-Link
MCX-N9XX-EVK	CMSIS-DAP	MCU-Link
MCX-W71-EVK	CMSIS-DAP	MCU-Link
MCX-W72-EVK	CMSIS-DAP	MCU-Link
MIMXRT1024-EVK	CMSIS-DAP	LPC-Link2
MIMXRT1040-EVK	CMSIS-DAP	LPC-Link2
MIMXRT1060-EVKB	CMSIS-DAP	LPC-Link2
MIMXRT1060-EVKC	CMSIS-DAP	MCU-Link
MIMXRT1160-EVK	CMSIS-DAP	LPC-Link2
MIMXRT1170-EVKB	CMSIS-DAP	MCU-Link
MIMXRT1180-EVK	CMSIS-DAP	MCU-Link
MIMXRT685-AUD-EVK	CMSIS-DAP	LPC-Link2
MIMXRT700-EVK	CMSIS-DAP	MCU-Link
RD-RW612-BGA	CMSIS-DAP	MCU-Link
TWR-KM34Z50MV3	P&E Micro	OpenSDA v1
TWR-KM34Z75M	P&E Micro	OpenSDA v1
TWR-KM35Z75M	CMSIS-DAP	OpenSDA v2
TWR-MC56F8200	P&E Micro	OSJTAG
TWR-MC56F8400	P&E Micro	OSJTAG

How to define IRQ handler in CPP files With MCUXpresso SDK, users could define their own IRQ handler in application level to override the default IRQ handler. For example, to override the default PIT_IRQHandler define in startup_DEVICE.s, application code like app.c can be implement like:

```
// c
void PIT_IRQHandler(void)
{
    // Your code
}
```

When application file is CPP file, like app.cpp, then extern "C" should be used to ensure the function prototype alignment.

```
// cpp
extern "C" {
    void PIT_IRQHandler(void);
}
void PIT_IRQHandler(void)
{
    // Your code
}
```

Repository-Layout SDK Package

The Repository-Layout SDK Package is downloaded and extracted the same way as the Classic SDK Package — see SDK Builder for how to obtain it. Once extracted, it uses the same SDK

workspace layout as the GitHub Repository SDK, so you get the same offline development experience as a full workspace checkout. This section walks through installing development tools, touring the workspace layout, building your first example, generating IDE projects for IAR or Keil MDK, and importing the package into the MCUXpresso for VS Code extension.

Development Tools Installation This guide explains how to install the essential tools for development with the MCUXpresso SDK.

Quick Start: Automated Installation (Recommended)

The **MCUXpresso Installer** is the fastest way to get started. It automatically installs all the basic tools you need.

1. **Download the MCUXpresso Installer** from: MCUXpresso Installer
2. **Run the installer** and select **"MCUXpresso SDK Developer"** from the menu
3. **Click Install** and let it handle everything automatically

Manual Installation

If you prefer to install tools manually or need specific versions, follow these steps:

Essential Tools

Git - Version Control

What it does: Manages code versions and downloads SDK repositories from GitHub.

Installation:

- Visit git-scm.com
- Download for your operating system
- Run installer with default settings
- **Important**: Make sure "Add Git to PATH" is selected during installation

Setup:

```
git config --global user.name "Your Name"
git config --global user.email "youremail@example.com"
```

Python - Scripting Environment

What it does: Runs build scripts and SDK tools.

Installation:

- Install Python **3.10 or newer** from python.org
- **Important**: Check "Add Python to PATH" during installation

West - SDK Management Tool

What it does: Manages SDK repositories and provides build commands. The west tool is developed by the Zephyr project for managing multiple repositories.

Installation:

```
pip install -U west
```

Minimum version: 1.2.0 or newer

Build System Tools

CMake - Build Configuration

What it does: Configures how your projects are built.

Recommended version: 3.30.0 or newer

Installation:

- **Windows**: Download .msi installer from cmake.org/download
- **Linux**: Use package manager or download from cmake.org
- **macOS**: Use Homebrew (brew install cmake) or download from cmake.org

Ninja - Fast Build System

What it does: Compiles your code quickly.

Minimum version: 1.12.1 or newer

Installation:

- **Windows**: Usually included, or download from ninja-build.org
- **Linux**: sudo apt install ninja-build or download binary
- **macOS**: brew install ninja or download binary

Ruby - IDE Project Generation (Optional)

What it does: Generates project files for IDEs like IAR and Keil.

When needed: Only if you want to use traditional IDEs instead of VS Code.

Installation: Follow the Ruby environment setup guide

Compiler Toolchains

Choose and install the compiler toolchain you want to use:

Toolchain	Best For	Download Link	Environment Variable
Arm GCC (Recommended)	Most users, free	Arm GNU Toolchain	ARMGCC_DIR
IAR EWARM	Professional development	IAR Systems	IAR_DIR
Keil MDK	Arm ecosystem	Arm Developer	MDK_DIR
Arm Compiler	Advanced optimization	Arm Developer	ARMCLANG_DIR
Code Warrior	DSC platforms	NXP CodeWarrior	CW_DIR
Xtensa	DSP core	Tensilica Tools	XCC_DIR

Setting Up Environment Variables

After toolchain installation, set an environment variable so the build system locates it:

Windows:

```
# Example for ARM GCC installed in C:\armgcc
setx ARMGCC_DIR "C:\armgcc"
```

Linux/macOS:

```
# Add to ~/.bashrc or ~/.zshrc
export ARMGCC_DIR="/usr"  # or your installation path
```

Verify Your Installation

After installation, verify everything works by opening a terminal/command prompt and running these commands:

```
# Check each tool - you should see version numbers
git --version
python --version
west --version
cmake --version
ninja --version
arm-none-eabi-gcc --version  # (if using ARM GCC)
```

Troubleshooting Installation Issues

"Command not found" errors:

- The tool isn't in your system PATH
- **Solution**: Add the installation directory to your PATH environment variable

Python/pip issues:

- Try using `python3` and `pip3` instead of `python` and `pip`
- On Windows, run the Command Prompt as an Administrator

Slow downloads:

- Add timeout option: `pip install -U west --default-timeout=1000`
- Use alternative mirror: `pip install -U west -i https://pypi.tuna.tsinghua.edu.cn/simple`

Workspace Structure

After you initialize your SDK workspace, it creates a specific directory structure that organizes all SDK components. This structure is identical for both GitHub Repository SDK and Repository-Layout SDK Package.

Top-Level Organization

```
your-sdk-workspace/
  manifests/        # West manifest repository
  mcuxsdk/          # Main SDK content
```

The `mcuxsdk/` directory serves as your primary working directory and contains all the SDK components.

SDK Component Layout

Based on the actual SDK structure, the main directories include:

Directory	Contents	Purpose
arch/	Architecture-specific files	ARM CMSIS, build configurations
cmake	Build system modules	CMake configuration and build rules
compo	Software components	Reusable software libraries and utilities
devices	Device support packages	MCU-specific headers, startup code, linker scripts
drivers	Peripheral drivers	Hardware abstraction layer for MCU peripherals
examp	Sample applications	Demonstration code and reference implementations
middle	Optional software stacks	Networking, graphics, security, and other libraries
rtos/	Operating system support	FreeRTOS integration
scripts	Build and utility scripts	West extensions and development tools
svd	Svd files for devices, this is optional because of large size. Customers run `west manifest config group.filter +optional` and `west update mcux-soc-svd` to get this folder.	

Example Organization

Examples follow a two-tier structure separating common code from board-specific implementations:

Common Example Files

```
examples/demo_apps/hello_world/
    CMakeLists.txt        # Build configuration
    example.yml           # Example metadata
    hello_world.c         # Application source code
    Kconfig               # Configuration options
    readme.md             # General documentation
```

Board-Specific Files

```
examples/_boards/your_board/demo_apps/hello_world/
    app.h                    # Board specific application header
    example_board_readme.md    # Board specific documentation
    hardware_init.c          # Board specific hardware initialization
    pin_mux.c                # Pin multiplexing configuration
    pin_mux.h                # Pin multiplexing header definitions
    hello_world.bin          # Pre-built binary for quick testing
    hello_world.mex          # MCUXpresso Config Tools project file
    prj.conf                 # Board specific Kconfig configuration
    reconfig.cmake           # Board specific cmake configuration overrides
```

Device Support Structure

Device support is organized hierarchically by MCU family:

```
devices/
  MCX/                  # MCU portfolio
    MCXW/               # MCU family
      MCXW235/          # Specific device
        MCXW235.h           # Device register definitions
        drivers/            # Device-specific drivers
        gcc/                # GNU toolchain files
        iar/                # IAR toolchain files
        mcuxpresso/         # MCUXpresso IDE files
        startup_MCXW235.c # Startup and vector table
        system_MCXW235.c  # System initialization
```

Middleware Organization

Middleware components are categorized by functionality and maintained in separate repositories. Based on the manifest files, common middleware categories include:

- **Connectivity**: USB, TCP/IP, industrial protocols
- **Security**: Cryptographic libraries, secure boot
- **Wireless**: Bluetooth, IEEE 802.15.4, Wi-Fi
- **Graphics**: Display drivers, UI frameworks
- **Audio**: Processing libraries, voice recognition
- **Machine Learning**: Inference engines, neural networks
- **Safety**: IEC60730B safety libraries
- **Motor Control**: Motor control and real-time control libraries

Documentation Structure

SDK documentation is distributed across multiple locations:

- docs/ - Core SDK documentation and build infrastructure
- Component repositories - API documentation and integration guides
- Board directories - Hardware-specific setup instructions

For complete documentation, refer to the online documentation.

Understanding Example Structure

Each example has **two README files**:

1. General README: examples/demo_apps/hello_world/readme.md

- What the example does
- General functionality description
- Common usage information

2. Board-Specific README: examples/_boards/{board_name}/demo_apps/hello_world/example_board_readme.md

- Board-specific setup instructions
- Hardware connections required

- Board-specific behavior notes

Tip: Always check both readme files - start with the general one, then read the board-specific one for detailed setup.

Building Your First Project This guide explains how to build and run your first SDK example project using the west build system. This applies to both GitHub Repository SDK and Repository-Layout SDK Package.

Prerequisites

- GitHub Repository SDK workspace initialized OR Repository-Layout SDK Package extracted
- Development board connected via USB
- Build tools installed per *Installation Guide*

Understanding Board Support

Before building, check whether your board is single-core or multicore, and which core IDs it supports:

```
west boards -b your_board
```

This prints the resolved device and, for multicore boards, the list of valid `core_ids` you'll need for the build command below. For a single-core board, no core ID is needed.

If you want to see every supported build configuration (toolchain/config combination) for a specific example instead, use:

```
west list_project -p examples/demo_apps/hello_world
```

This shows all supported build configurations. You can filter by toolchain:

```
west list_project -p examples/demo_apps/hello_world -t armgcc
```

`west list_project` is the most complete way to discover build commands across all boards and targets, but `west boards -b your_board` is the quicker way to look up just the board/core information you need once you already know which example you want to build.

Basic Build Process

Simple Build

Build the hello_world example with default settings:

```
west build -b your_board examples/demo_apps/hello_world
```

The default toolchain is armgcc, and the build system will select the first debug target as default if no config is specified.

Specifying Configuration

```
# Release build
west build -b your_board examples/demo_apps/hello_world --config release

# Debug build (default)
west build -b your_board examples/demo_apps/hello_world --config debug
```

Alternative Toolchains

```
# IAR toolchain
west build -b your_board examples/demo_apps/hello_world --toolchain iar

# Other toolchains as supported by the example
```

Multicore Applications

For multicore devices, west boards -b your_board (above) tells you which core IDs are valid. Specify the core either with -Dcore_id=:

```
west build -b evkbmimxrt1170 examples/demo_apps/hello_world --toolchain iar -Dcore_id=cm7 --config␣
↪flexspi_nor_debug
```

or more concisely by appending @<core_id> to the board name:

```
west build -b evkbmimxrt1170@cm7 examples/demo_apps/hello_world --toolchain iar --config flexspi_nor_
↪debug
```

Single-core boards don't need a core ID at all.

For multicore projects using sysbuild:

```
west build -b evkbmimxrt1170 --sysbuild ./examples/multicore_examples/hello_world/primary -Dcore_
↪id=cm7 --config flexspi_nor_debug --toolchain=armgcc -p always
```

Flash an Application

Flash the built application to your board:

```
west flash -r linkserver
```

Debug

Start a debug session:

```
west debug -r linkserver
```

Common Build Options

Clean Build

Force a complete rebuild:

```
west build -b your_board examples/demo_apps/hello_world -p always
```

Dry Run

See the commands that get executed without running them:

```
west build -b your_board examples/demo_apps/hello_world --dry-run
```

Device Variants

For boards supporting multiple device variants:

```
west build -b your_board examples/demo_apps/hello_world --device DEVICE_PART_NUMBER --config␣
↪release
```

Project Configuration

CMake Configuration Only

Run configuration without building:

```
west build -b your_board examples/demo_apps/hello_world -Dcore_id=cm7 --cmake-only -p
```

Interactive Configuration

Launch the configuration GUI:

```
west build -t guiconfig
```

Troubleshooting

Build Failures

Use pristine builds to resolve dependency issues:

```
west build -b your_board examples/demo_apps/hello_world -p always
```

Getting Help

View the help information for west build:

```
west build -h
```

Check Supported Configurations

To see available configuration options and board targets for an example, refer to the below command:

```
west list_project -p examples/demo_apps/hello_world
```

Next Steps

- Explore other examples in the SDK
- Learn about *Command Line Development* for advanced options
- Try *VS Code Development* for integrated development
- Refer *Workspace Structure* to understand the SDK layout

Run a Demo Using IAR The Repository-Layout SDK Package does not ship pre-generated IDE projects. Instead, you generate an IAR Embedded Workbench project on demand from the CMake build, the same way you would from a GitHub Repository SDK checkout.

Prerequisite: Ruby

IDE project generation is implemented in Ruby and is only needed if you want to use IAR instead of the command line or VS Code. See *Ruby - IDE Project Generation (Optional)* for setup instructions before continuing.

1. Generate the IAR project

If this is a pristine build, specify board, example, toolchain and core on the command line:

```
west build -b evkbmimxrt1170 examples/demo_apps/hello_world --toolchain iar -Dcore_id=cm7 --config␣
↪flexspi_nor_debug -p always -t guiproject
```

If you already built the example with `west build`, you can regenerate the project with the shorter form:

```
west build -t guiproject
```

The project files are generated into `mcuxsdk/build/iar`, using relative paths to refer to source files and include paths in the repository. For the full set of `guiproject` options, see IDE Project Generation.

Generate into a custom folder

By default the project is generated into `mcuxsdk/build/<toolchain>`. To generate into a different location instead — for example to keep projects for several examples or boards side by side — pass `-d` with the pristine build command:

```
west build -b evkbmimxrt1170 examples/demo_apps/hello_world --toolchain iar -Dcore_id=cm7 --config␣
↪flexspi_nor_debug -p always -t guiproject -d build_hello_world_iar
```

2. Open the project in IAR Embedded Workbench

Open the generated workspace or project file from:

```
mcuxsdk/build/iar
```

3. Build the demo application

1. Select the desired build target from the drop-down menu, for example **hello_world - flexspi_nor_debug**.
2. Click **Make** to build the demo application.
3. The build completes without errors.

4. Run the demo application

1. Open a terminal application on the PC, such as PuTTY or TeraTerm, and connect to the debug COM port (see *How to determine COM port*).
2. Click **Download and Debug** to flash and start debugging.
3. Click **Go** to run to the entry point and resume execution.
4. The terminal displays the demo application output.

Next steps

- *Run a demo using MDK* — the same flow for Keil MDK
- *Building Your First Project* — build and run from the command line

Run a Demo Using MDK The Repository-Layout SDK Package does not ship pre-generated IDE projects. Instead, you generate a Keil MDK (µVision) project on demand from the CMake build, the same way you would from a GitHub Repository SDK checkout.

Prerequisites

Ruby

IDE project generation is implemented in Ruby and is only needed if you want to use MDK instead of the command line or VS Code. See *Ruby - IDE Project Generation (Optional)* for setup instructions before continuing.

CMSIS device pack

Cortex Microcontroller Software Interface Standard (CMSIS) device packs must be installed in MDK to fully support the device from a debug perspective, including memory map information, register definitions, and flash programming algorithms. In µVision, select the **Pack Installer** icon and install the pack for your device before opening the generated project.

1. Generate the MDK project

If this is a pristine build, specify board, example, toolchain and core on the command line:

```
west build -b evkbmimxrt1170 examples/demo_apps/hello_world --toolchain mdk -Dcore_id=cm7 --config␣
↪flexspi_nor_debug -p always -t guiproject
```

If you already built the example with `west build`, you can regenerate the project with the shorter form:

```
west build -t guiproject
```

The project files are generated into `mcuxsdk/build/mdk`, using relative paths to refer to source files and include paths in the repository. For the full set of `guiproject` options, see IDE Project Generation.

Generate into a custom folder

By default the project is generated into `mcuxsdk/build/<toolchain>`. To generate into a different location instead — for example to keep projects for several examples or boards side by side — pass `-d` with the pristine build command:

```
west build -b evkbmimxrt1170 examples/demo_apps/hello_world --toolchain mdk -Dcore_id=cm7 --config␣
↪flexspi_nor_debug -p always -t guiproject -d build_hello_world_mdk
```

2. Open the project in µVision

Open the generated `.uvmpw` workspace file from:

```
mcuxsdk/build/mdk
```

3. Build the demo application

1. Select **Rebuild** to build the demo project.
2. The build completes without errors.

4. Run the demo application

1. Open a terminal application on the PC, such as PuTTY or TeraTerm, and connect to the debug COM port (see *How to determine COM port*).
2. Click the **Download** button to download the application to the target.
3. Click the **Start/Stop Debug Session** button to enter the debug session.
4. Click the **Run** button to start the application.
5. The terminal displays the demo application output.

Next steps

- *Run a demo using IAR* — the same flow for IAR Embedded Workbench
- *Building Your First Project* — build and run from the command line

MCUXpresso for VS Code Development This guide covers using MCUXpresso for VS Code extension to build, debug, and develop SDK applications with an integrated development environment.

Prerequisites

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

Extension Installation

Install MCUXpresso for VS Code

The MCUXpresso for VS Code extension provides integrated development capabilities for MCUXpresso SDK projects. Refer to the MCUXpresso for VS Code documentation for detailed installation and setup instructions.

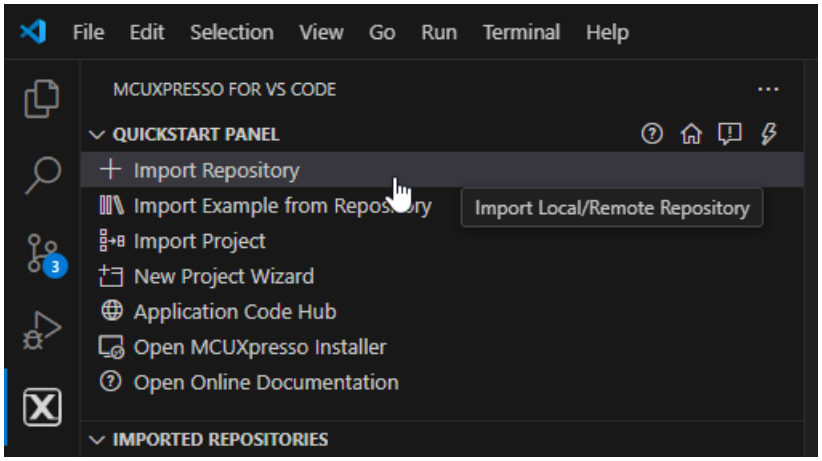
SDK Import and Setup

Import Methods

The SDK can be imported in several ways. The MCUXpresso for VS Code extension supports both GitHub Repository SDK and Repository-Layout SDK Package distributions.

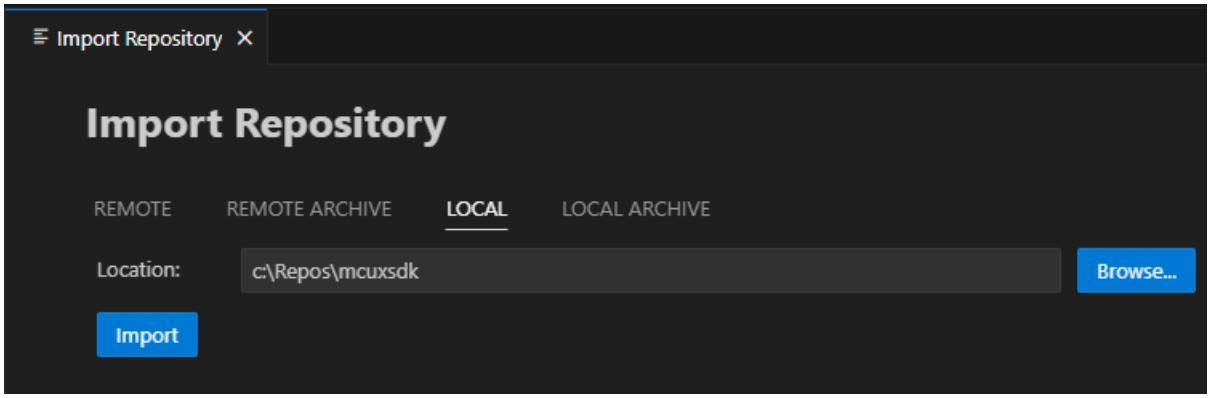
Import GitHub Repository SDK

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

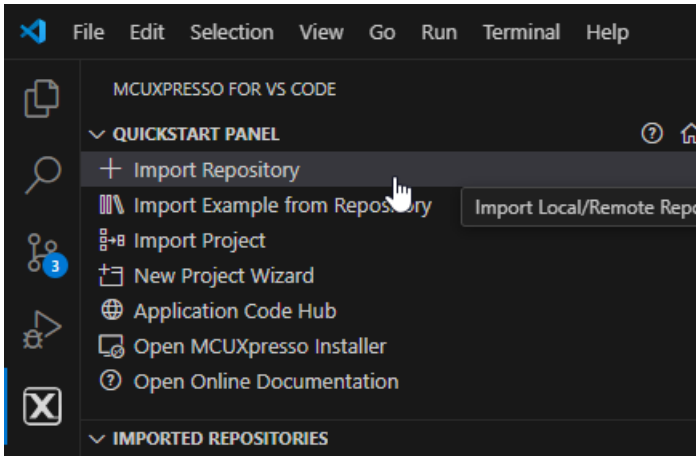


Note: You can import the SDK in several ways. Refer to the MCUXpresso for VS Code documentation for details.

Select **Local** if you've already obtained the SDK according to *setting up the repo*. Select your location and click **Import**.

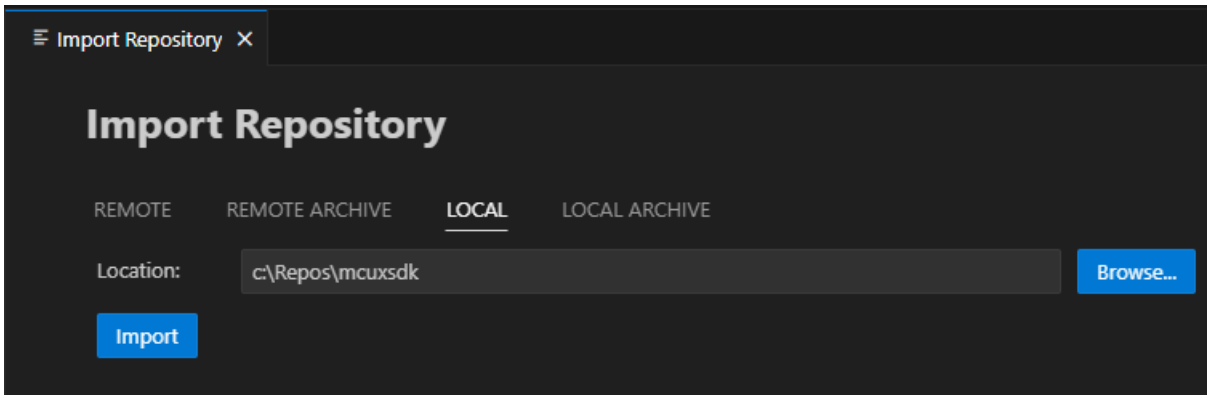


Import Repository-Layout SDK Package

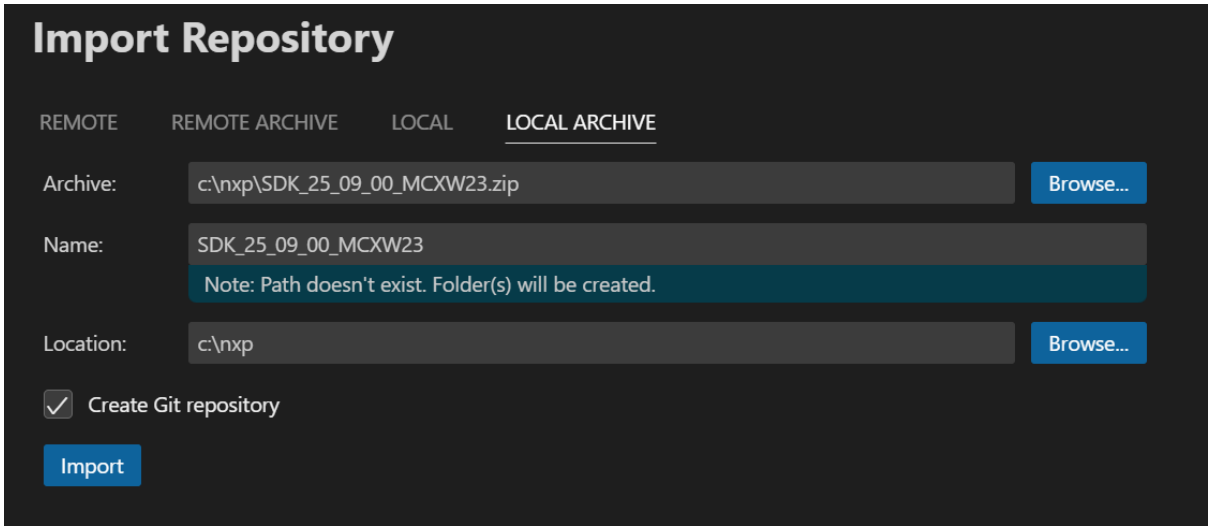


Click **Import Repository** from the **QUICKSTART PANEL**

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



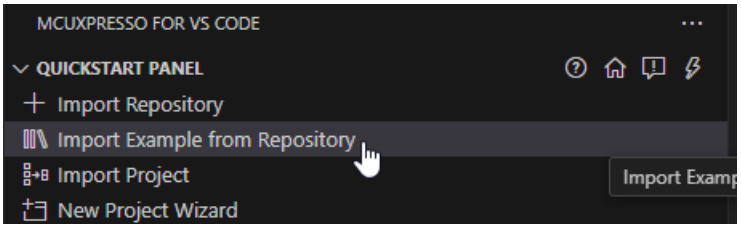
Else if the SDK is ZIP archive, select **Local Archive**, browse to the downloaded SDK ZIP file, fill the link of expect location, then click **Import**.



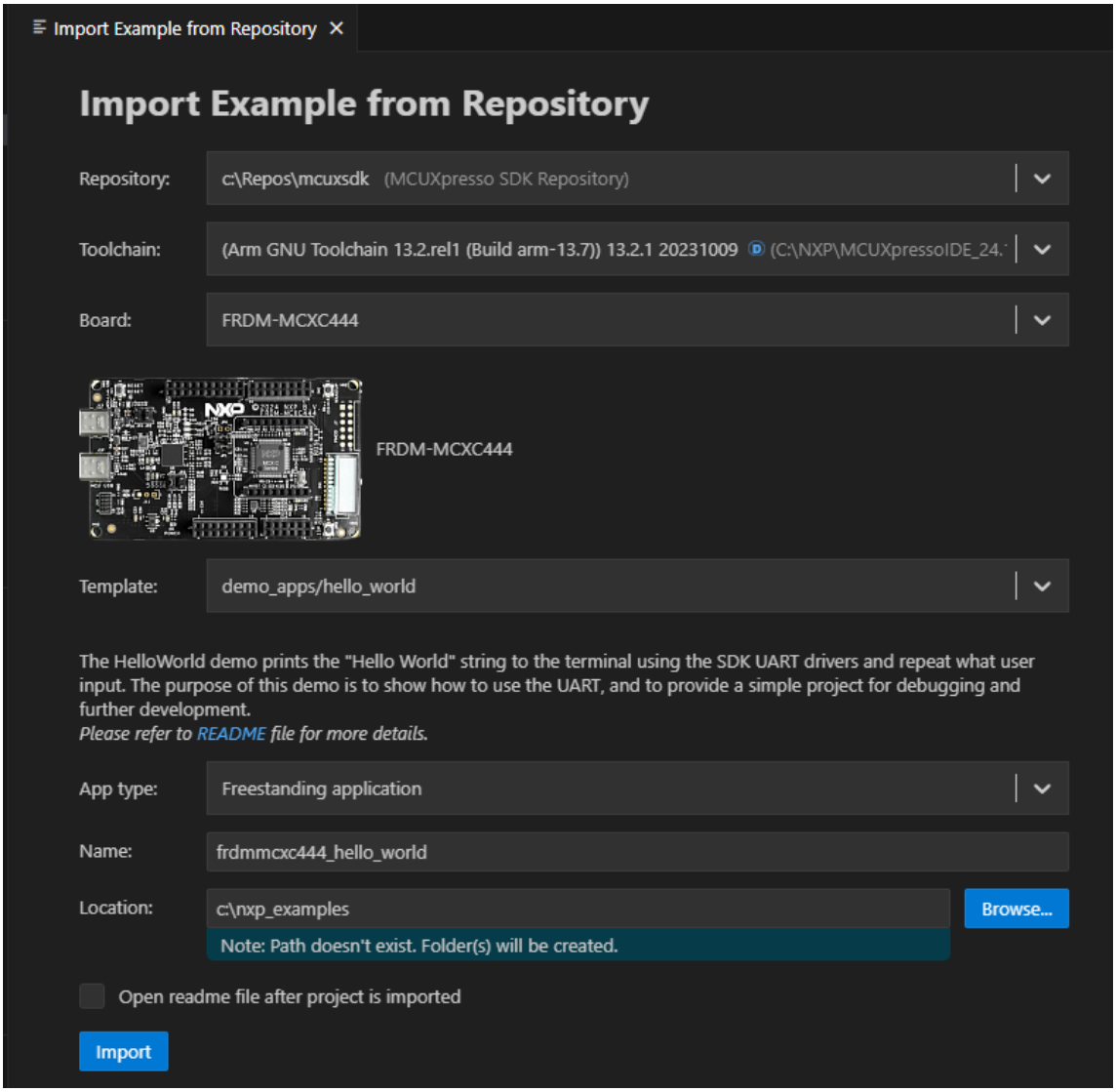
Building Example Applications

Import Example Project

1. Click **Import Example from Repository** from the **QUICKSTART PANEL**



2. Configure project settings:
   - **MCUXpresso SDK**: Select your imported SDK
   - **Arm GNU Toolchain**: Choose toolchain
   - **Board**: Select your target development board
   - **Template**: Choose example category
   - **Application**: Select specific example (e.g., hello_world)
   - **App type**: Choose between Repository applications or Freestanding applications
3. Click **Import**



Application Types

Repository Applications:

- Located inside the MCUXpresso SDK
- Integrated with SDK workspace

Freestanding Applications:

- Imported to user-defined location
- Independent of SDK location

Trust Confirmation

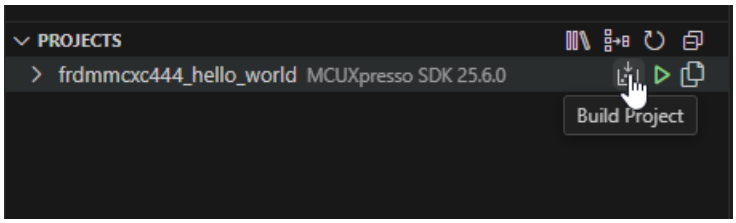
VS Code will prompt you to confirm if the imported files are trusted. Click **Yes** to proceed.

Building Projects

Build Process

1. Navigate to **PROJECTS** view
2. Find your project

3. Click the **Build Project** icon

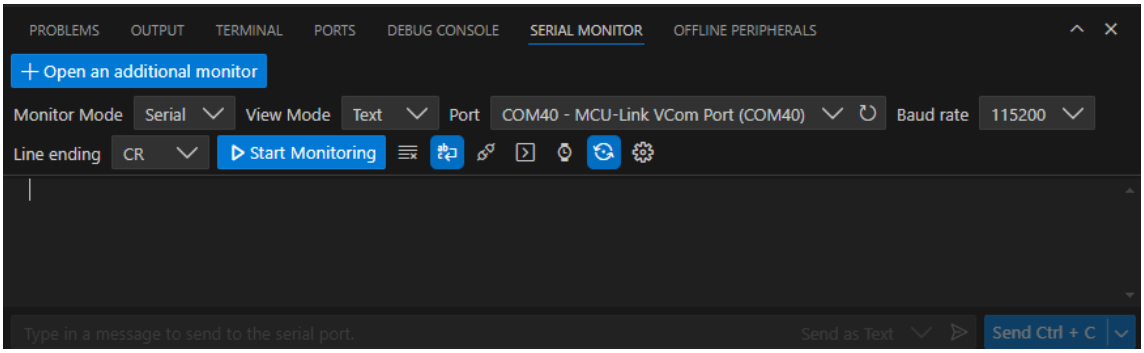


The integrated terminal will display build output at the bottom of the VS Code window.

Running and Debugging

Serial Monitor Setup

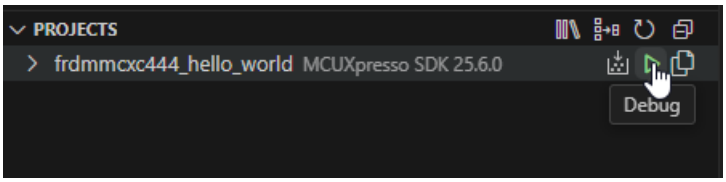
1. Open **Serial Monitor** from VS Code's integrated terminal



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

Debug Session

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



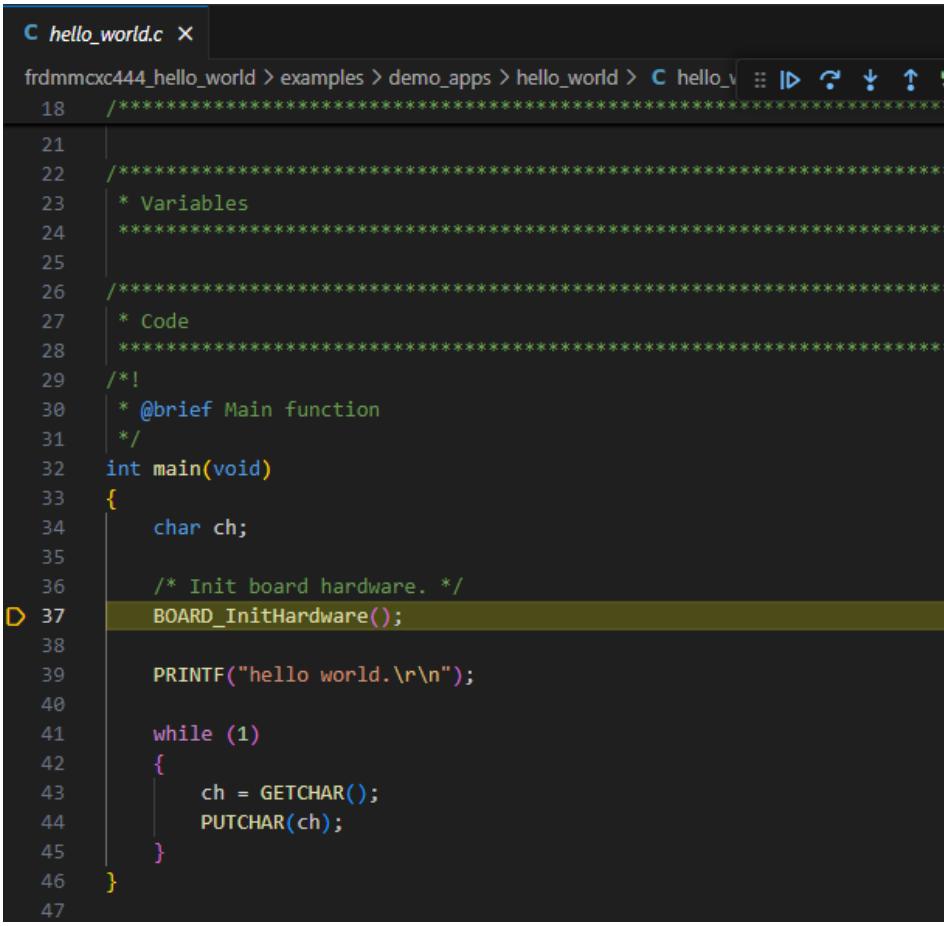
The debug session will begin with debug controls initially at the top of the interface.

Debug Controls

Use the debug controls to manage execution:

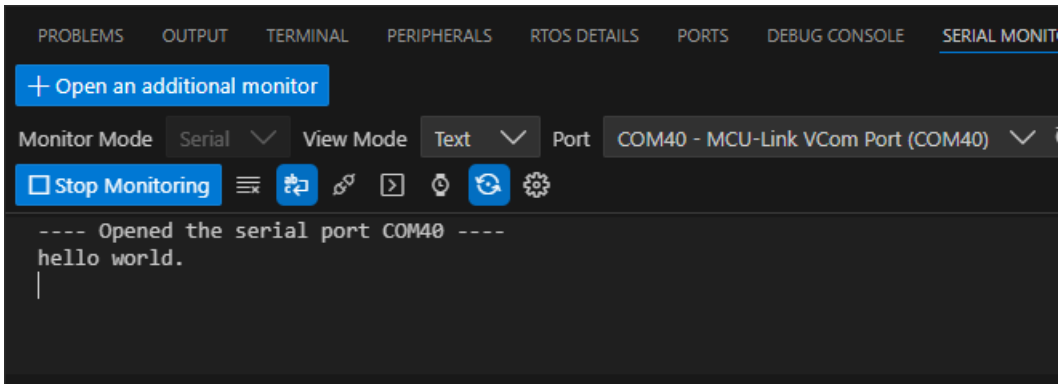
- **Continue**: Resume code execution
- **Step controls**: Navigate through code

- **Stop**: Terminate debug session



Monitor Output

Observe application output in the **Serial Monitor** to verify correct operation.



Debug Probe Support

For comprehensive information on debug probe support and configuration, refer to the MCUXpresso for VS Code Debug documentation.

Project Configuration

Workspace Management

The extension integrates with the MCUXpresso SDK workspace structure, providing access to:

- Example applications

- Board configurations
- Middleware components
- Build system integration

Multi-Project Support

The PROJECTS view allows management of multiple imported projects within the same workspace.

Troubleshooting

Import Issues

SDK not detected:

- Verify SDK workspace is properly initialized
- Ensure all required repositories are updated
- Check SDK manifest files are present

Project import failures:

- Confirm board support exists for selected example
- Verify toolchain installation
- Check example compatibility with selected board

Build Problems

Build failures:

- Check integrated terminal for error messages
- Verify all dependencies are installed
- Ensure toolchain is properly configured

Debug Issues

Debug session fails:

- Verify board connection via USB
- Check debug probe drivers are installed
- Confirm build completed successfully

Serial monitor problems:

- Verify correct VCom port selection
- Check baud rate configuration (115200)
- Ensure board drivers are installed

Integration with Command Line

MCUXpresso for VS Code integrates with the underlying west build system, allowing seamless integration with command line workflows described in *Command Line Development*.

Advanced Features

Project Types

The extension supports both repository-based and freestanding project types, providing flexibility in project organization and SDK integration.

Build System Integration

The extension leverages the MCUXpresso SDK build system, providing access to all build configurations and options available through command line tools.

Next Steps

- Explore additional examples in the SDK
- Review *Command Line Development* for advanced build options
- Refer to the MCUXpresso for VS Code documentation for detailed documentation
- Learn about *SDK Architecture* for better understanding of the development environment

1.4 Getting Started with MCUXpresso SDK GitHub

1.4.1 Getting Started with MCUXpresso SDK Repository

Welcome to the **GitHub Repository SDK Guide**. This documentation provides instructions for setting up and working with the MCUXpresso SDK distributed in a **multi-repository model**. The SDK is distributed across multiple GitHub repositories and managed using the **Zephyr West** tool, enabling modular development and streamlined workflows.

Overview

The GitHub Repository SDK approach offers:

- **Modular Structure**: Multiple repositories for flexibility and scalability.
- **Zephyr West Integration**: Simplified repository management and synchronization.
- **Cross-Platform Support**: Designed for MCUXpresso SDK development environments.

Benefits of the Multi-Repository Approach

- **Scalability**: Easily add or update components without impacting the entire SDK.
- **Collaboration**: Enables distributed development across teams and repositories.
- **Version Control**: Independent versioning for components ensures better stability.
- **Automation**: Zephyr West simplifies dependency handling and repository synchronization.

Setup and Configuration

Follow these steps to prepare your development environment:

GitHub Repository Setup This guide explains how to initialize your MCUXpresso SDK workspace from GitHub repositories using the west tool. The GitHub Repository SDK uses multiple repositories hosted on GitHub to provide modular, flexible development.

Prerequisites

Verify the requirements:

System Requirements:

- Python 3.8 or later
- Git 2.25 or later
- CMake 3.20 or later
- Build tools for your target platform

Verification Commands:

```
python --version    # Should show 3.8+
git --version       # Should show 2.25+
cmake --version     # Should show 3.20+
west --version      # Should show west tool installation
```

Workspace Initialization

The GitHub Repository SDK uses the Zephyr west tool to manage multiple repositories containing different SDK components.

Step 1: Initialize Workspace

Create and initialize your SDK workspace from GitHub:

Get the latest SDK from main branch:

```
west init -m https://github.com/nxp-mcuxpresso/mcuxsdk-manifests.git mcuxpresso-sdk
```

Get SDK at specific revision:

```
west init -m https://github.com/nxp-mcuxpresso/mcuxsdk-manifests.git mcuxpresso-sdk --mr {revision}
```

Note: Replace {revision} *with the desired release tag, such as* v25.09.00

Step 2: Choose Your Repository Update Strategy

Navigate to the SDK workspace:

```
cd mcuxpresso-sdk
```

The west tool manages multiple GitHub repositories containing different SDK components. You have two options for downloading:

Option A: Download All Repositories (Complete SDK)

Download all SDK repositories for comprehensive development:

```
west update
```

This command downloads all the repositories defined in the manifest from GitHub. Initial download takes several minutes and requires ~7 GB of disk space.

Best for:

- Exploring the complete SDK

- Multi-board development projects
- Comprehensive middleware evaluation

Option B: Targeted Repository Download (Recommended)

Download only repositories needed for your specific board or device to save time and disk space:

```
# For specific board development
west update_board --set board your_board_name

# For specific device family development
west update_board --set device your_device_name

# List available repositories before downloading
west update_board --set board your_board_name --list-repo
```

Best for:

- Single board development
- Faster setup and reduced disk usage
- Focused development workflows

Examples:

```
# Update only repositories for FRDM-MCXW23 board
west update_board --set board frdmmcxw23

# Update only repositories for MCXW23 device family
west update_board --set device mcxw23
```

Step 3: Verify Installation

Confirm successful setup:

```
# Verify workspace structure
ls -la
# Should show: manifests/ and mcuxsdk/ directories

# Test build system
west list_project -p examples/demo_apps/hello_world
# Should display available build configurations
```

Advanced Repository Management

The west extension command `update_board` provides advanced repository management capabilities for optimized workspace setup with GitHub repositories.

Board-Specific Setup

Update only repositories required for a specific board:

```
# Update only repositories for specific board, e.g., frdmmcxw23
west update_board --set board frdmmcxw23

# List available repositories for the board before updating
west update_board --set board frdmmcxw23 --list-repo
```

Device-Specific Setup

Update only repositories required for a specific device family:

```
# Update only repositories for specific device, e.g., MCXW235
west update_board --set device mcxw23

# List available repositories for the device family
west update_board --set device mcxw23 --list-repo
```

Custom Configuration

For advanced users who want to create custom repository combinations:

```
# Use custom configuration file
west update_board --set custom path/to/custom-config.yml

# Generate custom configuration template
cp manifests/boards/custom.yml.template my-custom-config.yml
```

Benefits of Targeted Setup

Reduced Download Size

- Download only components needed for your target board or device
- Significantly faster initial setup for focused development
- Typical reduction from 7 GB to 2GB

Optimized Workspace

- Cleaner workspace with relevant components only
- Reduced disk space usage
- Faster repository operations

Flexible Development

- Switch between different board configurations easily
- Maintain separate workspaces for different projects
- Include optional components as needed

Repository Information

Before setting up your workspace, you can explore what repositories are available:

```
# Display repository information in console
west update_board --set board frdmmcxw23 --list-repo

# Export repository information to YAML file for reference
west update_board --set board frdmmcxw23 --list-repo -o board-repos.yml
```

This command lists all the available repositories with descriptions and outlines the included components in the workspace.

Package Generation (Optional)

The `update_board` command can also generate ZIP packages for offline distribution:

```
# Generate board-specific SDK package
west update_board --set board frdmmcxw23 -o frdmmcxw23-sdk.zip
```

Note: Package generation is primarily intended for creating custom SDK distributions. For regular development, use the workspace update commands without the `-o` option.

Workspace Management

Updating Your Workspace

Keep your SDK current with latest updates from GitHub:

For Complete SDK Workspace:

```
# Update manifest repository
cd manifests
git pull

# Update all component repositories
cd ..
west update
```

For Targeted Workspace:

```
# Update manifest repository
cd manifests
git pull

# Update board-specific repositories
cd ..
west update_board --set board your_board_name
```

Workspace Status

Check workspace synchronization status:

```
# Show status of all repositories
west status

# Show detailed information about repositories
west list
```

Troubleshooting

Network Issues:

- Use `west update --keep-descendants` for partial failures
- Configure Git credentials for private repositories
- Check firewall settings for Git protocol access

Permission Issues:

- Ensure write permissions in workspace directory
- Run commands without sudo/administrator privileges
- Verify Git SSH key configuration for authenticated access

Disk Space:

- Full SDK workspace requires approximately 7-8 GB
- Targeted workspace typically requires 1-2 GB
- Use board-specific setup to reduce workspace size

Repository Management Issues:

- Verify board/device names match available configurations
- Check that custom YAML files follow the correct template format

- Use --list-repo to verify available repositories before setup

Next Steps

With your workspace initialized:

1. Review *Workspace Structure* to understand the layout
2. Build your first project with *First Build Guide*
3. Explore *Development Workflows MCUXPresso VSCode* or *Development Workflows Command Line* for the details on project setup and execution

For advanced repository management, see the west tool documentation.

Prebuilt Binary Blobs Some SDK components ship with prebuilt binary files (.a, .lib, .bin, etc.) that are **not included in the git repository itself**. Instead they are fetched on demand from a dedicated blob repository using the west blobs command.

This keeps the main SDK checkout small and fast while still making the binaries available immediately when you need them.

When do you need to fetch blobs?

You typically need blobs when:

- You are building an example that links against a prebuilt library (e.g. a machine learning inference engine, a wireless stack library, or a graphics middleware).
- After a fresh west init + west update, the build fails with a linker error about a missing .a or .lib file.
- You run west blobs check and see MISSING entries.

Quick start

Run these commands from your SDK workspace root (the directory that contains manifests/ and mcuxsdk/):

```
# 1. See what blobs are available and whether they are already present
west blobs check

# 2. Fetch any missing blobs
west blobs fetch

# 3. Confirm everything is present
west blobs check
```

A green result looks like:

```
mcu-sdk-examples: 1078/1078 entries: OK
```

Fetch blobs for a specific project only

If you only need blobs for one component, pass the west project name:

```
west blobs fetch mcu-sdk-examples
```

Use `west blobs list` to see available project names and their blob files:

```
west blobs list
```

License

By fetching blobs you accept the license terms bundled with each blob set. The applicable license file is located alongside `mcux_blobs.yml` in the relevant SDK subdirectory (for example `mcuxsdk/examples/LICENSE`).

Some blob sets require explicit license acceptance. If a blob has `click-through: True`, `west blobs fetch` will prompt you to confirm before downloading.

Keeping blobs up to date

After running `west update` (which updates the SDK source), re-run:

```
west blobs fetch
```

Blobs that are already present and whose sha256 matches are skipped automatically; only new or changed blobs are downloaded.

Troubleshooting

Build error: cannot find `-lsomething` or missing `.a` / `.bin`

```
west blobs fetch        # fetch all missing blobs
west blobs check        # verify
```

Re-fetch a corrupted or incomplete blob

```
# Remove locally cached blobs for one project and re-download
west blobs clean mcu-sdk-examples
west blobs fetch mcu-sdk-examples
```

Network / proxy issues

`west blobs fetch` downloads files over HTTPS. If your network requires a proxy, set the standard environment variables before running the command:

```
export HTTPS_PROXY=http://your-proxy:port
west blobs fetch
```

Checking without downloading

```
west blobs check        # shows OK or MISSING per entry; does not download
west blobs list         # lists all declared blobs; does not download
```

Next steps

- *Building Your First Project* — build and run an SDK example
- *Exploring the SDK* — workspace layout and example organization

Explore SDK Structure and Content

Learn about the organization of the SDK and its components:

SDK Architecture Overview The MCUXpresso SDK uses a modular architecture where software components are distributed across multiple repositories hosted on GitHub and managed through the west tool. This approach provides flexibility, maintainability, and enables selective component inclusion.

Repository Organization

Based on the manifest structure, the SDK consists of four main repository categories:

Manifest Repository

The manifest repo (mcuxsdk-manifests) contains the west.yml manifest file that tracks all other repositories in the SDK.

Base Repositories

Recorded in submanifests/base.yml and loaded in the root west.yml manifest file. These are the foundational repositories that build the SDK:

- **Devices**: MCU-specific support packages
- **Examples**: Demonstration applications and code samples
- **Boards**: Board support packages

Middleware Repositories

Recorded in the submanifests/middleware subdirectory, categorized according to functionality:

- **Connectivity**: Networking stacks, USB, and communication protocols
- **Security**: Cryptographic libraries and secure boot components
- **Wireless**: Bluetooth, IEEE 802.15.4, and other wireless protocols
- **Graphics**: Display drivers and UI frameworks
- **Audio**: Audio processing and voice recognition libraries
- **Machine Learning**: AI inference engines and neural network libraries
- **Safety**: IEC60730B safety libraries
- **Motor Control**: Motor control and real-time control libraries

Internal Repositories

Recorded in submanifests/internal.yml and grouped into the “bifrost” group. These are only visible to NXP internal developers and hosted on NXP internal git servers.

Repository Hosting

Public repositories are hosted on GitHub under these organizations:

- nxp-mcuxpresso

- NXP
- nxp-zephyr

Internal repositories are hosted on NXP's private Git infrastructure.

Benefits of This Architecture

Selective Integration: Projects include only required components, reducing memory footprint and build complexity.

Independent Versioning: Each component maintains its own release cycle and version control.

Community Collaboration: Public repositories accept community contributions through standard Git workflows.

Scalable Maintenance: Component owners can update their repositories without affecting the entire SDK.

Workspace Management

The west tool manages repository synchronization, version tracking, and workspace updates. All repositories are checked out under the `mcuxsdk/` directory with their designated paths defined in the manifest files.

Development Workflows

Get started with building and running projects:

Command Line Development This guide covers developing with the MCUXpresso SDK using command line tools and the west build system. This workflow applies to both GitHub Repository SDK and Repository-Layout SDK Package distributions.

Prerequisites

- GitHub Repository SDK workspace initialized OR Repository-Layout SDK Package extracted
- Development tools installed per *Installation Guide*
- Target board connected via USB

Understanding Board Support

Use the west extension to discover available examples for your board:

```
west list_project -p examples/demo_apps/hello_world
```

This shows all supported build configurations. You can filter by toolchain:

```
west list_project -p examples/demo_apps/hello_world -t armgcc
```

Basic Build Commands

Standard Build Process

Build with default settings (armgcc toolchain, first debug config):

```
west build -b your_board examples/demo_apps/hello_world
```

Specifying Build Configuration

```
# Release build
west build -b your_board examples/demo_apps/hello_world --config release

# Debug build with specific toolchain
west build -b your_board examples/demo_apps/hello_world --toolchain iar --config debug
```

Multicore Applications

For multicore devices, specify the core ID:

```
west build -b evkbmimxrt1170 examples/demo_apps/hello_world --toolchain iar -Dcore_id=cm7 --config␣
↪flexspi_nor_debug
```

For multicore projects using sysbuild:

```
west build -b evkbmimxrt1170 --sysbuild ./examples/multicore_examples/hello_world/primary -Dcore_
↪id=cm7 --config flexspi_nor_debug --toolchain=armgcc -p always
```

Shield Support

For boards with shields:

```
west build -b mimxrt700evk --shield a8974 examples/issdk_examples/sensors/fxls8974cf/fxls8974cf_poll -
↪Dcore_id=cm33_core0
```

Advanced Build Options

Clean Builds

Force a complete rebuild:

```
west build -b your_board examples/demo_apps/hello_world -p always
```

Dry Run

See what commands would be executed:

```
west build -b your_board examples/demo_apps/hello_world --dry-run
```

Device Variants

For boards supporting multiple device variants:

```
west build -b your_board examples/demo_apps/hello_world --device MK22F12810 --config release
```

Project Configuration

CMake Configuration Only

Run configuration without building:

```
west build -b evkbmimxrt1170 examples/demo_apps/hello_world -Dcore_id=cm7 --cmake-only -p
```

Interactive Configuration

Launch the configuration GUI:

```
west build -t guiconfig
```

Flashing and Debugging

Flash Application

Flash the built application to your board:

```
west flash -r linkserver
```

Debug Session

Start a debugging session:

```
west debug -r linkserver
```

IDE Project Generation

To use a traditional IDE instead of the command line or VS Code, generate an IDE project from the CMake build with `-t guiproject`:

- *Run a demo using IAR*
- *Run a demo using MDK*

Both guides cover the Ruby dependency required for IDE project generation.

Troubleshooting

Build Failures

Use pristine builds to resolve dependency issues:

```
west build -b your_board examples/demo_apps/hello_world -p always
```

Toolchain Issues

Verify environment variables are set correctly:

```
# Check ARM GCC
echo $ARMGCC_DIR
arm-none-eabi-gcc --version

# Check IAR (if using)
echo $IAR_DIR
```

Getting Help

Display help information:

```
west build -h
west flash -h
west debug -h
```

Check Supported Configurations

If unsure about supported options for an example:

```
west list_project -p examples/demo_apps/hello_world
```

Best Practices

Project Organization

- Keep custom projects outside the SDK tree
- Use version control for your application code
- Document any SDK modifications

Build Efficiency

- Use `-p always` for clean builds when troubleshooting
- Leverage `--dry-run` to understand build processes
- Use specific configs and toolchains to reduce build time

Development Workflow

1. Start with existing examples closest to your requirements
2. Copy and modify rather than building from scratch
3. Test with hello_world before moving to complex examples
4. Use configuration tools for pin muxing and clock setup

Next Steps

- Explore *VS Code Development* for integrated development experience
- Review *Workspace Structure* to understand SDK organization
- Refer build system documentation for advanced configurations

Using MCUXpresso Config Tools MCUXpresso Config tools provide a user-friendly way to configure hardware initialization of your projects. This guide explains the basic workflow with the MCUXpresso SDK west build system and the Config Tools.

Prerequisites

- GitHub Repository SDK workspace initialized OR Repository-Layout SDK Package extracted
- MCUXpresso Config Tools standalone installed (version 25.09 or above)
- MCUXpresso SDK Project that can be successfully built

Board Files

MCUXpresso Config Tools generate source files for the board. These files include pin_mux.c/h and clock_config.c/h. The files contain initialization code functions that reflect the hardware configuration in the Config Tools. Within the SDK codebase, these files are specific for the board and either shared by multiple example projects or specific for one example. Open or import the configuration from the SDK project in the Config Tools and customize the settings to match the custom board or specific project use case and regenerate the code. See *User Guide for MCUXpresso Config Tools (Desktop)* (document GSMCUXCTUG) for details.

Note: When opening the configuration for SDK example projects, the board files may be shared across multiple examples. To ensure a separate copy of the board configuration files exists, create a freestanding project with copied board files.

Visual Studio Code

To open the configuration in Visual Studio Code, use the context menu for the project to access Config Tools. See MCUXpresso Extension Documentation for details.
Otherwise, use the manual workflow described in detail in the following section.

Manual Workflow

Use the following steps:

1. Before using Config Tools, run the west command to get the project information for Config Tools from the SDK project files, for example:

   ```
   west cfg_project_info -b lpcxpresso55s69 ...mcuxsdk/examples/demo_apps/hello_world/ -Dcore_
   ↪id=cm33_core0
   ```

   This results in the creation of the project information json file that is searched by the config tools when the configuration is created. The parameters of the command should match the build parameters that will be used for the project.

2. Launch the MCUXpresso Config Tools and in the **Start development** wizard, select **Create a new configuration based on the existing IDE/Toolchain project**. Select the created "cfg_tools" subfolder as a project folder (for example: ...mcuxsdk/examples/demo_apps/hello_world/cfg_tools/).

Updating the SDK West project

Note: Updating project is supported with Config Tools V25.12 or newer only.

Changes in the Config tools generated source code modules may require adjustments to the toolchain project to ensure a successful build. These changes may mean, for example, adding the newly generated files, adding include paths, required drivers, or other SDK components. This section describes how to manually resolve the changes needed in the project within the toolchain projects based on the SDK project managed by the West tool.

After the configuration in the Config Tools is finished, write updated files to the disk using the 'Update Code' command. The written files include a json file with the required changes for the toolchain project.

To resolve the changes in the project in the terminal, launch the west command that updates the project. For example:

```
west cfg_resolve -b lpcxpresso55s69 ...mcuxsdk/examples/demo_apps/hello_world/ -Dcore_id=cm33_core0
```

This command updates the appropriate cmake and kconfig files to address the changes. After this, the application can be built.

Note: The cfg_resolve command supports additional arguments. Launch the *west cfg_resolve -h* command to get the list and description.

1.5 Release Notes

1.5.1 MCUXpresso SDK Release Notes

Development tools

The MCUXpresso SDK was tested with following development tools. Same versions or above are recommended.

- MCUXpresso IDE, Rev. 25.06.xx

- IAR Embedded Workbench for Arm, version is 9.70.4
- Keil MDK, version is 5.43a
- MCUXpresso for VS Code v26.06
- GCC Arm Embedded Toolchain 14.2.x

Supported development systems

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

Development boards	MCU devices				
FRDM-MCXA36	MCXA355VLH, MCXA356VLL, MCXA365VLQ, MCXA366VPN	MCXA355VLL, MCXA356VLQ, MCXA365VPN,	MCXA355VLQ, MCXA356VPN, MCXA366VLH,	MCXA355VPN, MCXA365VLH, MCXA366VLL,	MCXA356VLH, MCXA365VLL, **MCXA366VLQ**,

MCUXpresso SDK release package

The MCUXpresso SDK release package content is aligned with the silicon subfamily it supports. This includes the boards, CMSIS, devices, middleware, and RTOS support.

Device support The device folder contains the whole software enablement available for the specific System-on-Chip (SoC) subfamily. This folder includes clock-specific implementation, device register header files, device register feature header files, and the system configuration source files. Included with the standard SoC support are folders containing peripheral drivers, toolchain support, and a standard debug console. The device-specific header files provide a direct access to the microcontroller peripheral registers. The device header file provides an overall SoC memory mapped register definition. The folder also includes the feature header file for each peripheral on the microcontroller. The toolchain folder contains the startup code and linker files for each supported toolchain. The startup code efficiently transfers the code execution to the main() function.

Board support The boards folder provides the board-specific demo applications, driver examples, and middleware examples.

Demo application and other examples The demo applications demonstrate the usage of the peripheral drivers to achieve a system level solution. Each demo application contains a readme file that describes the operation of the demo and required setup steps. The driver examples demonstrate the capabilities of the peripheral drivers. Each example implements a common use case to help demonstrate the driver functionality.

RTOS

FreeRTOS Real-time operating system for microcontrollers from Amazon

Middleware

CMSIS DSP Library The MCUXpresso SDK is shipped with the standard CMSIS development pack, including the prebuilt libraries.

IEC60730B Safety Library NXP IEC60730B Safety Library

PSA Test Suite Arm Platform Security Architecture Test Suite

TF-M Trusted Firmware - M Library

mbedTLS mbedtls SSL/TLS library v3.x

NXP PSA CRYPTO DRIVER PSA crypto driver for crypto library integration via driver wrappers

NXP SGI PKC NXP Secure General Interface Public Key Cryptography middleware for hardware-accelerated asymmetric crypto operations.

USB Host, Device, OTG Stack See the MCUXpresso SDK USB Stack User's Guide (document MCUXSDKUSBSUG) for more information.

Peripheral devices tested with USB Host stack

Table 1 provides a list of USB devices tested with the USB Host stack.

Device type	Device
USB HUB	BELKIN F5U233BELKIN F5U304BELKIN F5U307BELKIN F4U040UNITEK Y-2151Z-TEK ZK032AHYUNDAI HY-HB608
USB flash drive	ADATA C008 32 GBADATA S102 8 GADATA S102 16 GVerbatim STORE N GO USB Device 8 GKingston DataTraveler DT101 G2SanDisk Cruzer Blade 8 GBUnisplendour 1 GImation 2 GBV-mux 2 GBSanmina-SCI 128 MCorporate Express 1 GTOSHIBA THUHYBS-008G 8 GTranscend JF700 8 GNetac U903 16 GSSK SFD205 8 GBRex 4 GBSAMSUNG USB3.0 16GB
USB card reader/	SSK TF adapterKawau Multi Card ReaderKawau TF adapterKawau SDHC cardUSB Mouse DELL MS111-PDELL M066U0ADELL MUAVDEL8TARGUS AMU76APDELL MD56U0DELL MS111-TRAPOO M110
USB Keyboard	DELL SK8135DELL SK8115

MCU Boot Open source MCU Bootloader.

LVGL LVGL Open Source Graphics Library

LittleFS LittleFS filesystem stack

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

Metering Metering Library

FreeMASTER FreeMASTER communication driver for 32-bit platforms.

File systemFatfs The FatFs file system is integrated with the MCUXpresso SDK and can be used to access either the SD card or the USB memory stick when the SD card driver or the USB Mass Storage Device class implementation is used.

emWin The MCUXpresso SDK is pre-integrated with the SEGGER emWin GUI middleware. The AppWizard provides developers and designers with a flexible tool to create stunning user interface applications, without writing any code.

Release contents

Provides an overview of the MCUXpresso SDK release package contents and locations.

Deliverable	Location
Boards	INSTALL_DIR/boards
Demo Applications	INSTALL_DIR/boards/<board_name>/demo_apps
Driver Examples	INSTALL_DIR/boards/<board_name>/driver_examples
eIQ examples	INSTALL_DIR/boards/<board_name>/eiq_examples
Board Project Template for MCUXpresso IDE NPW	INSTALL_DIR/boards/<board_name>/project_template
Driver, SoC header files, extension header files and feature header files, utilities	INSTALL_DIR/devices/<device_name>
CMSIS drivers	INSTALL_DIR/devices/<device_name>/cmsis_drivers
Peripheral drivers	INSTALL_DIR/devices/<device_name>/drivers
Toolchain linker files and startup code	INSTALL_DIR/devices/<device_name>/<toolchain_nam
Utilities such as debug console	INSTALL_DIR/devices/<device_name>/utilities
Device Project Template for MCUXpresso IDE NPW	INSTALL_DIR/devices/<device_name>/project_templat
CMSIS Arm Cortex-M header files, DSP library source	INSTALL_DIR/CMSIS
Components and board device drivers	INSTALL_DIR/components
RTOS	INSTALL_DIR/rtos
Release Notes, Getting Started Document and other documents	INSTALL_DIR/docs
Tools such as shared cmake files	INSTALL_DIR/tools
Middleware	INSTALL_DIR/middleware

Known Issues

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

Cannot add SDK components into FreeRTOS projects

It is not possible to add any SDK components into FreeRTOS project using the MCUXpresso IDE New Project wizard.

1.6 ChangeLog

1.6.1 MCUXpresso SDK Changelog

AOI

[2.0.2]

- Improvements
  - Release peripheral from reset if necessary in init function.

[2.0.1]

- Bug Fixes
  - MISRA C-2012 issue fixed: rule 10.8, 2.2.

[2.0.0]

- Initial version.

CACHE LPCAC

[2.2.2]

- Bug Fixes
  - Fixed L1CACHE_InvalidateCodeCache() leaving the cache held cleared. LPCAC_CTRL[CLR_LPCAC] is sticky, so setting it kept the cache invalidated/disabled until written back to 0. The function now sets and then clears the bit (with a memory barrier in between) so the cache is invalidated and left in a valid, operational state.

[2.2.1]

- Improvements
  - Add memory barrier when enabling/disabling cache.

[2.2.0]

- Improvements
  - Used new add macros FSL_FEATURE_SYSCON_HAS_LPCAC_CTRL_PARITY_MISS_EN_BIT and FSL_FEATURE_SYSCON_HAS_LPCAC_CTRL_PARITY_FAULT_EN_BIT to support some platforms which PARITY_MISS_EN and PARITY_FAULT_EN bit may be reserved.

[2.1.1]

- Bug Fixes
  - Fixed an issue of L1CACHE_InvalidateCodeCache() function, to clean cache the LPCAC_CTRL[CLR_LPCAC] should be set not clear.

[2.1.0]

- Improvements
  - Supported more features, such as write buffer contron, write buffer limit and so on.

[2.0.0]

- Initial version.

CDOG

[2.1.3]

- Re-design multiple instance IRQs and Clocks
- Add fix for RESTART command errata

[2.1.2]

- Support multiple IRQs
- Fix default CONTROL values

[2.1.1]

- Remove bit CONTROL[CONTROL_CTRL].

[2.1.0]

- Rename CWT to CDOG.

[2.0.2]

- Fix MISRA-2012 issues.

[2.0.1]

- Fix doxygen issues.

[2.0.0]

- Initial version.

CLOCK

[2.0.2]

- Added configurable timeout support for endless while loop.

[2.0.1]

- Add FRO HF 240M support.

[2.0.0]

- Initial version.

MCX_CMC

[2.6.0]

- New Features
  - Added feature macro FSL_FEATURE_MCX_CMC_HAS_DBGCTL_REG to be compatible with platforms where CMC has no DBGCTL register.

[2.5.0]

- New features
  - Update MCX_CMC driver to be compatible with new platforms.

[2.4.0]

- New features
  - Update MCX_CMC driver to be compatible with new platforms.

[2.3.0]

- Improvements
  - Added macros to support some device have BSR_SCR bit field.

[2.2.3]

- Improvements
  - Clear SCB SCR[SLEEPDEEP] bitfield after wakeup.

[2.2.2]

- Improvements
  - Fixed the violation of MISRA C-2012 rules.

[2.2.1]

- Improvements
  - Updated _cmc_system_reset_interrupt_enable, _cmc_system_reset_interrupt_flag and _cmc_system_reset_sources to support new added bit field.
- Bug Fixes
  - Fixed issue in CMC_PowerOffSRAMAllMode() and CMC_PowerOffSRAMLowPowerOnly() which overwrite reserved bit fields.

[2.2.0]

- Improvements
  - Added feature macro “FSL_FEATURE_MCX_CMC_HAS_NO_FLASHCR_WAKE” to support some devices where FLASHCR[WAKE] is reserved.

[2.1.0]

- Improvements
  - Added macros to support some devices(such as MCXA family) that only support one power domain.

[2.0.0]

- Initial version.

COMMON

[2.6.7]

- Improvements
  - EnableIRQ/DisableIRQ: Use IRQSTEER_GetInstIdxByIRQ() to determine IRQSTEER instance index instead of simple division. Supports multiple IRQSTEER instances with different interrupt counts.

[2.6.6]

- Improvements
  - Support Cortex M55.

[2.6.5]

- Bug Fixes
  - Fixed the issue that the function SDK_DelayAtLeastUs may underflow and cause a long delay when the input parameter is small and the system clock is low.

[2.6.4]

- New Features
  - Add macros to tag deprecated features and experimental features.

[2.6.3]

- New Features
  - Added bit mask inversion macros to avoid type promotion.
  - Added register operation macros.
- Improvements
  - Make function MSDK_EnableCpuCycleCounter compatible with CMSIS-5 and CMSIS-6.
- Bug Fixes
  - Fixed build issue of CMSIS PACK BSP example caused by CMSIS 6.1 issue.

[2.6.2]

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule for implicit conversions in boolean contexts

[2.6.1]

- Improvements
  - Support Cortex M23.

[2.6.0]

- Bug Fixes
  - Fix CERT-C violations.

[2.5.0]

- New Features
  - Added new APIs InitCriticalSectionMeasurementContext, DisableGlobalIRQEx and EnableGlobalIRQEx so that user can measure the execution time of the protected sections.

[2.4.3]

- Improvements
  - Enable irqs that mount under irqsteer interrupt extender.

[2.4.2]

- Improvements
  - Add the macros to convert peripheral address to secure address or non-secure address.

[2.4.1]

- Improvements
  - Improve for the macro redefinition error when integrated with zephyr.

[2.4.0]

- New Features
  - Added EnableIRQWithPriority, IRQ_SetPriority, and IRQ_ClearPendingIRQ for ARM.
  - Added MSDK_EnableCpuCycleCounter, MSDK_GetCpuCycleCount for ARM.

[2.3.3]

- New Features
  - Added NETC into status group.

[2.3.2]

- Improvements
  - Make driver aarch64 compatible

[2.3.1]

- Bug Fixes
  - Fixed MAKE_VERSION overflow on 16-bit platforms.

[2.3.0]

- Improvements
  - Split the driver to common part and CPU architecture related part.

[2.2.10]

- Bug Fixes
  - Fixed the ATOMIC macros build error in cpp files.

[2.2.9]

- Bug Fixes
  - Fixed MISRA C-2012 issue, 5.6, 5.8, 8.4, 8.5, 8.6, 10.1, 10.4, 17.7, 21.3.
  - Fixed SDK_Malloc issue that not allocate memory with required size.

[2.2.8]

- Improvements
  - Included stddef.h header file for MDK tool chain.
- New Features:
  - Added atomic modification macros.

[2.2.7]

- Other Change
  - Added MECC status group definition.

[2.2.6]

- Other Change
  - Added more status group definition.
- Bug Fixes
  - Undef __VECTOR_TABLE to avoid duplicate definition in cmsis_clang.h

[2.2.5]

- Bug Fixes
  - Fixed MISRA C-2012 rule-15.5.

[2.2.4]

- Bug Fixes
  - Fixed MISRA C-2012 rule-10.4.

[2.2.3]

- New Features
  - Provided better accuracy of SDK_DelayAtLeastUs with DWT, use macro SDK_DELAY_USE_DWT to enable this feature.
  - Modified the Cortex-M7 delay count divisor based on latest tests on RT series boards, this setting lets result be closer to actual delay time.

[2.2.2]

- New Features
  - Added include RTE_Components.h for CMSIS pack RTE.

[2.2.1]

- Bug Fixes
  - Fixed violation of MISRA C-2012 Rule 3.1, 10.1, 10.3, 10.4, 11.6, 11.9.

[2.2.0]

- New Features
  - Moved SDK_DelayAtLeastUs function from clock driver to common driver.

[2.1.4]

- New Features
  - Added OTFAD into status group.

[2.1.3]

- Bug Fixes
  - MISRA C-2012 issue fixed.
    - Fixed the rule: rule-10.3.

[2.1.2]

- Improvements
  - Add SUPPRESS_FALL_THROUGH_WARNING() macro for the usage of suppressing fallthrough warning.

[2.1.1]

- Bug Fixes
  - Deleted and optimized repeated macro.

[2.1.0]

- New Features
  - Added IRQ operation for XCC toolchain.
  - Added group IDs for newly supported drivers.

[2.0.2]

- Bug Fixes
  - MISRA C-2012 issue fixed.
    - Fixed the rule: rule-10.4.

[2.0.1]

- Improvements
  - Removed the implementation of LPC8XX Enable/DisableDeepSleepIRQ() function.
  - Added new feature macro switch "FSL_FEATURE_HAS_NO_NONCACHEABLE_SECTION" for specific SoCs which have no noncacheable sections, that helps avoid an unnecessary complex in link file and the startup file.
  - Updated the align(x) to **attribute**(aligned(x)) to support MDK v6 armclang compiler.

[2.0.0]

- Initial version.

CRC

[2.1.0]

- Bug fix:
  - Choosing CRC clocks from CRC clock array according to instance instead of hardcoded value.

[2.0.5]

- Bug fix:
  - Fix CERT-C issue with boolean-to-unsigned integer conversion.

[2.0.4]

- Improvements
  - Release peripheral from reset if necessary in init function.

[2.0.3]

- Bug fix:
  - Fix MISRA issues.

[2.0.2]

- Bug fix:
  - Fix MISRA issues.

[2.0.1]

- Bug fix:
  - DATA and DATALL macro definition moved from header file to source file.

[2.0.0]

- Initial version.

CTIMER

[2.3.6]

- Bug Fixes
  - Fix CERT INT30-C issue.

[2.3.5]

- Bug Fixes
  - MISRA C-2012 issue fixed: rule 10.7

[2.3.4]

- Bug Fixes
  - Fixed ERRATA ERR053024 CTIMER will enter interrupt twice when function clock much slower than bus clock.

[2.3.3]

- Bug Fixes
  - Fix CERT INT30-C INT31-C issue.
  - Make API CTIMER_SetupPwm and CTIMER_UpdatePwmDutycycle return fail if pulse width register overflow.

[2.3.2]

- Bug Fixes
  - Clear unexpected DMA request generated by RESET_PeripheralReset in API CTIMER_Init to avoid trigger DMA by mistake.

[2.3.1]

- Bug Fixes
  - MISRA C-2012 issue fixed: rule 10.7 and 12.2.

[2.3.0]

- Improvements
  - Added the CTIMER_SetPrescale(), CTIMER_GetCaptureValue(), CTIMER_EnableResetMatchChannel(), CTIMER_EnableStopMatchChannel(), CTIMER_EnableRisingEdgeCapture(), CTIMER_EnableFallingEdgeCapture(), CTIMER_SetShadowValue(),APIs Interface to reduce code complexity.

[2.2.2]

- Bug Fixes
  - Fixed SetupPwm() API only can use match 3 as period channel issue.

[2.2.1]

- Bug Fixes
  - Fixed use specified channel to setting the PWM period in SetupPwmPeriod() API.
  - Fixed Coverity Out-of-bounds issue.

[2.2.0]

- Improvements
  - Updated three API Interface to support Users to flexibly configure the PWM period and PWM output.
- Bug Fixes
  - MISRA C-2012 issue fixed: rule 8.4.

[2.1.0]

- Improvements
  - Added the CTIMER_GetOutputMatchStatus() API Interface.
  - Added feature macro for FSL_FEATURE_CTIMER_HAS_NO_CCR_CAP2 and FSL_FEATURE_CTIMER_HAS_NO_IR_CR2INT.

[2.0.3]

- Bug Fixes
  - MISRA C-2012 issue fixed: rule 10.3, 10.4, 10.6, 10.7 and 11.9.

[2.0.2]

- New Features
  - Added new API “CTIMER_GetTimerCountValue” to get the current timer count value.
  - Added a control macro to enable/disable the RESET and CLOCK code in current driver.
  - Added a new feature macro to update the API of CTimer driver for lpc8n04.

[2.0.1]

- Improvements
  - API Interface Change
    * Changed API interface by adding CTIMER_SetupPwmPeriod API and CTIMER_UpdatePwmPulsePeriod API, which both can set up the right PWM with high resolution.

[2.0.0]

- Initial version.

DAC

[2.2.0]

- New Features
  - Added support for configuring the analog output buffer bypass.
  - Added support for selecting the internal reference current source.
  - Added support for configuring the internal reference current trim.

[2.1.3]

- Improvements
  - ‘dac_config_t’ already contains a member ‘enableOpampBuffer’, but it is not used. This update uses ‘enableOpampBuffer’ to control the configuration of GCR[BUF_EN].

[2.1.2]

- Improvements
  - Release peripheral from reset if necessary in init function.

[2.1.1]

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

[2.1.0]

- New Features
  - Added support for period trigger mode.
  - Added support for sync trigger between dac instances.
  - Added support for configuring DAC sync cycles.
  - Added support for internal reference current selection.
  - Enabled buffer mode manually for K4 series board.

[2.0.2]

- Bug Fixes
  - Fixed MISRA C-2012 rule 10.3 and rule 17.7.

[2.0.1]

- New Features
  - Added a control macro to enable/disable the CLOCK code in current driver.

[2.0.0]

- Initial version.

EDMA

[2.10.14]

- Improvements
  - Applied ERRATA 52315.

[2.10.13]

- Improvements
  - Introduced the version-neutral name driver.edma_unified for the unified eDMA driver (which serves the eDMA3/eDMA4/eDMA5 IP versions), renamed the driver directory to drivers/edma_unified, and set FSL_COMPONENT_ID to platform.drivers.edma_unified. The previous driver.edma4 Kconfig component and the FSL_EDMA_DRIVER_EDMA4 macro are retained as deprecated aliases, so existing projects (including the shipped eDMA examples) keep building without changes; new projects should use driver.edma_unified / FSL_EDMA_DRIVER_UNIFIED. The C API, edma_handle_t, registers, and the IP-specific edma4_*/edma5_* TCD identifiers are unchanged.

[2.10.12]

- Bug Fixes
  - Fixed dynamic scatter/gather mid-flight submit on eDMA4/eDMA5: resolve the TCD link in software under a quiescent fence, since these IPs removed the CSR[ESG] read-back coherency model.

[2.10.11]

- Bug Fixes
  - Fixed CERT INT31-C and CERT INT30-C violations in edma4 driver.

[2.10.10]

- Bug Fixes
  - Fixed EDMA_StartTransfer could read an incorrect address when checking the channelmux status, potentially causing a hard fault issue.

[2.10.9]

- Bug Fixes
  - Add new api EDMA_TcdInit to avoid destroying code logic by reordering blocks in the toolchain.

[2.10.8]

- Bug Fixes
  - Fixed coverity issues with CERT INT30-C, CERT INT31-C compliance.
  - Fixed incorrect enabling of preemption capability issue.

[2.10.7]

- Improvements
  - Add condition to fix build warnings(array subscript 4 is above array bounds of 'edma_handle_t *[4][64]')
- Bug Fixes
  - Fixed the EDMA header index retrieval error caused by done bit calculation mistake issue.

[2.10.6]

- Improvements
  - Add macro FSL_FEATURE_EDMA_HAS_EDMA_TCD_CLOCK_ENABLE to enable tcd clocks in EDMA_Init function.

[2.10.5]

- Bug Fixes
  - Fixed memory convert would convert NULL as zero address issue.

[2.10.4]

- Improvements
  - Add new MP register macros to ensure compatibility with different devices.
  - Add macro DMA_CHANNEL_ARRAY_STEPn to adapt to complex addressing of edma tcd registers.

[2.10.3]

- Bug Fixes
  - Clear interrupt status flags in EDMA_CreateHandle to avoid triggering interrupt by mistake.

[2.10.2]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 10.3.

[2.10.1]

- Bug Fixes
  - Fixed EDMA_GetRemainingMajorLoopCount may return wrong value issue.
  - Fixed violations of the MISRA C-2012 rules 13.5, 10.4.

[2.10.0]

- Improvements
  - Modify the structures edma_core_mp_t, edma_core_channel_t, edma_core_tcd_t to adapt to edma5.
  - Add TCD register macro to facilitate confirmation of tcd type.
  - Modfiy the mask macro to a fixed value.
  - Add EDMA_TCD_TYPE macro to determine edma tcd type.
  - Add extension API to the following API to determine edma tcd type.
    - EDMA_ConfigChannelSoftwareTCD -> EDMA_ConfigChannelSoftwareTCDExt
    - EDMA_TcdReset -> EDMA_TcdResetExt
    - EDMA_TcdSetTransferConfig -> EDMA_TcdSetTransferConfigExt
    - EDMA_TcdSetMinorOffsetConfig -> EDMA_TcdSetMinorOffsetConfigExt
    - EDMA_TcdSetChannelLink -> EDMA_TcdSetChannelLinkExt
    - EDMA_TcdSetBandWidth -> EDMA_TcdSetBandWidthExt
    - EDMA_TcdSetModulo -> EDMA_TcdSetModuloExt
    - EDMA_TcdEnableAutoStopRequest -> EDMA_TcdEnableAutoStopRequestExt
    - EDMA_TcdEnableInterrupts -> EDMA_TcdEnableInterruptsExt
    - EDMA_TcdDisableInterrupts -> EDMA_TcdDisableInterruptsExt
    - EDMA_TcdSetMajorOffsetConfig -> EDMA_TcdSetMajorOffsetConfigExt

[2.9.2]

- Improvements
  - Remove tcd alignment check in API that is low level and does not necessarily use scather/gather mode.

[2.9.1]

- Bug Fixes
  - Deinit channel request source before set channel mux.

[2.9.0]

- Improvements
  - Release peripheral from reset if necessary in init function.
- Bug Fixes
  - Fixed the variable type definition error issue.
  - Fixed doxygen warning.
  - Fixed violations of MISRA C-2012 rule 18.1.

[2.8.1]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 10.3

[2.8.0]

- Improvements
  - Added feature FSL_FEATURE_EDMA_HAS_NO_CH_SBR_SEC to separate DMA without SEC bitfield.

[2.7.1]

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 10.3, 10.4, 11.6, 11.8, 14.3,.

[2.7.0]

- Improvements
  - Use more accurate DMA instance based feature macros.
- New Features
  - Add new APIs EDMA_PrepareTransferTCD and EDMA_SubmitTransferTCD, which support EDMA transfer using TCD.

[2.6.0]

- Improvements
  - Modify the type of parameter channelRequestSource from dma_request_source_t to int32_t in the EDMA_SetChannelMux.

[2.5.3]

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 10.3, 10.4, 11.6, 20.7, 12.2, 20.9, 5.3, 10.8, 8.4, 9.3.

[2.5.2]

- Improvements
  - Applied ERRATA 51327.

[2.5.1]

- Bug Fixes
  - Fixed the EDMA_ResetChannel function cannot reset channel DONE/ERROR status.

[2.5.0]

- Improvements
  - Added feature FSL_FEATURE_EDMA_HAS_NO_SBR_ATTR_BIT to separate DMA without ATTR bitfield.
  - Added api EDMA_GetChannelSystemBusInformation to gets the channel identification and attribute information on the system bus interface.
- Bug Fixes
  - Fixed the ESG bit not set in scatter gather mode issue.
  - Fixed the DREQ bit configuration missed in single transfer issue.
  - Cleared the interrupt status before invoke callback to avoid miss interrupt issue.
  - Removed disableRequestAfterMajorLoopComplete from edma_transfer_config_t structure as driver will handle it.
  - Fixed the channel mux configuration not compatible issue.
  - Fixed the out of bound access in function EDMA_DriverIRQHandler.

[2.4.4]

- Bug Fixes
  - Fixed comments by replacing STCD with TCD
  - Fixed the TCD overwrite issue when submit transfer request in the callback if there is a active TCD in hardware.

[2.4.3]

- Improvements
  - Added FSL_FEATURE_MEMORY_HAS_ADDRESS_OFFSET to convert the address between system mapped address and dma quick access address.
- Bug Fixes
  - Fixed the wrong tcd done count calculated in first TCD interrupt for the non scatter gather case.

[2.4.2]

- Bug Fixes
  - Fixed the wrong tcd done count calculated in first TCD interrupt by correct the initial value of the header.
  - Fixed violations of MISRA C-2012 rule 10.3, 10.4.

[2.4.1]

- Bug Fixes
  - Added clear CITER and BITER registers in EDMA_AbortTransfer to make sure the TCD registers in a correct state for next calling of EDMA_SubmitTransfer.
  - Removed the clear DONE status for ESG not enabled case to aovid DONE bit cleared unexpectedly.

[2.4.0]

- Improvements
  - Added api EDMA_EnableContinuousChannelLinkMode to support continuous link mode.
  - Added apis EDMA_SetMajorOffsetConfig/EDMA_TcdSetMajorOffsetConfig to support major loop address offset feature.
  - Added api EDMA_EnableChannelMinorLoopMapping for minor loop offset feature.
  - Removed the reduntant IRQ Handler in edma driver.

[2.3.2]

- Improvements
  - Fixed HIS ccm issue in function EDMA_PrepareTransferConfig.
  - Fixed violations of MISRA C-2012 rule 11.6, 10.7, 10.3, 18.1.
- Bug Fixes
  - Added ACTIVE & BITER & CITER bitfields to determine the channel status to fixed the issue of the transfer request cannot submit by function EDMA_SubmitTransfer when channel is idle.

[2.3.1]

- Improvements
  - Added source/destination address alignment check.
  - Added driver IRQ handler support for multi DMA instance in one SOC.

[2.3.0]

- Improvements
  - Added new api EDMA_PrepareTransferConfig to allow different configurations of width and offset.
- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 10.4, 10.1.
  - Fixed the Coverity issue regarding out-of-bounds write.

[2.2.0]

- Improvements
  - Added peripheral-to-peripheral support in EDMA driver.

[2.1.9]

- Bug Fixes
  - Fixed MISRA issue: Rule 10.7 and 10.8 in function EDMA_DisableChannelInterrupts and EDMA_SubmitTransfer.
  - Fixed MISRA issue: Rule 10.7 in function EDMA_EnableAsyncRequest.

[2.1.8]

- Bug Fixes
  - Fixed incorrect channel preemption base address used in EDMA_SetChannelPreemptionConfig API which causes incorrect configuration of the channel preemption register.

[2.1.7]

- Bug Fixes
  - Fixed incorrect transfer size setting.
    - Added 8 bytes transfer configuration and feature for RT series;
    - Added feature to support 16 bytes transfer for Kinetis.
  - Fixed the issue that EDMA_HandleIRQ would go to incorrect branch when TCD was not used and callback function not registered.

[2.1.6]

- Bug Fixes
  - Fixed KW3X MISRA Issue.
    - Rule 14.4, 10.8, 10.4, 10.7, 10.1, 10.3, 13.5, and 13.2.
- Improvements
  - Cleared the IRQ handler unavailable for specific platform with macro FSL_FEATURE_EDMA_MODULE_CHANNEL_IRQ_ENTRY_SHARED_OFFSET.

[2.1.5]

- Improvements
  - Improved EDMA IRQ handler to support half interrupt feature.

[2.1.4]

- Bug Fixes
  - Cleared enabled request, status during EDMA_Init for the case that EDMA is halted before reinitialization.

[2.1.3]

- Bug Fixes
  - Added clear DONE bit in IRQ handler to avoid overwrite TCD issue.
  - Optimized above solution for the case that transfer request occurs in callback.

[2.1.2]

- Improvements
  - Added interface to get next TCD address.
  - Added interface to get the unused TCD number.

[2.1.1]

- Improvements
  - Added documentation for eDMA data flow when scatter/gather is implemented for the EDMA_HandleIRQ API.
  - Updated and corrected some related comments in the EDMA_HandleIRQ API and edma_handle_t struct.

[2.1.0]

- Improvements
  - Changed the EDMA_GetRemainingBytes API into EDMA_GetRemainingMajorLoopCount due to eDMA IP limitation (see API comments/note for further details).

[2.0.5]

- Improvements
  - Added pubweak DriverIRQHandler for K32H844P (16 channels shared).

[2.0.4]

- Improvements
  - Added support for SoCs with multiple eDMA instances.
  - Added pubweak DriverIRQHandler for KL28T DMA1 and MCIMX7U5_M4.

[2.0.3]

- Bug Fixes
  - Fixed the incorrect pubweak IRQHandler name issue, which caused re-definition build errors when client set his/her own IRQHandler, by changing the 32-channel IRQHandler name to DriverIRQHandler.

[2.0.2]

- Bug Fixes
  - Fixed incorrect minorLoopBytes type definition in _edma_transfer_config struct, and defined minorLoopBytes as uint32_t instead of uint16_t.

[2.0.1]

- Bug Fixes
  - Fixed the eDMA callback issue (which did not check valid status) in EDMA_HandleIRQ API.

[2.0.0]

- Initial version.

EIM

[2.1.0]

- New Features
  - Enhanced EIM driver support for extended memory channels (16-30).
  - Added new API EIM_InjectDataWordBitError() and EIM_GetDataWordBitMask() to support more data words (2-6).
- Improvements
  - Change eim_memory_channel_t to uint32_t.

[2.0.3]

- Bug Fixes
  - Fixed s_eimResets variable declaration issue.

[2.0.2]

- Improvements
  - Reset the peripheral during initialization, otherwise some platforms may not work.
- Bug Fixes
  - Fixed incorrect register access in EIM_GetDataBitMask().

[2.0.1]

- Improvements
  - Update driver to support fewer channel.
- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 10.3.

[2.0.0]

- Initial version.

EQDC

[2.3.2]

- Bug Fix
- Fixed violations of the CERT INT31-C.
- Fixed violations of the MISRA C-2012 rules 10.1, 10.3, 10.8.

[2.3.1]

- Bug Fix
- Fixed CTRL2[CMODE] field overwritten in API EQDC_Init.

[2.3.0]

- Improvements
- Add feature macro to support platforms which do not have compare interrupt.

[2.2.3]

- Bug Fix
- Clear Revolution Counter Register(REV) in init function to prevent its value not equal to zero after reset.

[2.2.2]

- Improvements
- Release peripheral from reset if necessary in init function.

[2.2.1]

- Bug Fix
- Fixed violations of the MISRA C-2012 rules 20.9.

[2.2.0]

- New features
- Supported the feature that the position counter to be initialized by Index Event Edge Mark.

[2.1.0]

- Bug Fix
- Fixed typo in interrupt enumeration values.
  - Improvements
- Supported Count Direct Change interrupt.
- Removed unused parameter in user configuration.
- Supported ERRATA_051383 check, the CTRL[DMAEN] can't be cleared.

[2.0.1]

- Bug Fix
- Fixed violations of the MISRA C-2012 rules 10.3, 10.6, 10.8, 14.4, 16.4.

[2.0.0]

- Initial version.

ERM

[2.0.4]

- New Features
  - Enhanced ERM driver support for extended memory channels (16-30).
- Improvements
  - Change erm_memory_channel_t to uint32_t.

[2.0.3]

- Bug Fixes
  - Fixed s_ermResets variable declaration issue.

[2.0.2]

- Improvements
  - Reset the peripheral during initialization, otherwise some platforms may not work.
- Bug Fixes
  - Only keep bit 0-3 of ERM_GetInterruptStatus() as it may get other channel results in higher bits.

[2.0.1]

- Improvements
  - Update driver to support fewer channel.
- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 10.3.

[2.0.0]

- Initial version.

FLEXCAN

[2.16.0]

- Improvements
  - Added four new members to flexcan_config_t so that the previously hard-coded register values can now be configured by the application:
    - enableThreeSamplingMode - controls CTRL1[SMP]; default true (backward compatible).
    - disableBusOffAutoRecovery - controls CTRL1[BOFFREC]; default false (backward compatible).
    - txArbitrationStartDelay - controls CTRL2[TASD] (0–31 Tq); default 0x16 (backward compatible).
    - enableEntireArbitrationCompare - controls CTRL2[EACEN]; default true (backward compatible).

  - Remove above unconditionally overwritten hard-coded registers value from FLEXCAN_Reset.

[2.15.2]

- Bug Fixes
  - Fixed violations of the CERT INT31-C.

[2.15.1]

- Improvements
  - Wait for RX Message Buffer busy state cleared before reading in following APIs.
    - FLEXCAN_ReadRxMb
    - FLEXCAN_ReadFDRxMb
  - Simplify RX Message Buffer handling sequence in interrupt handler FLEXCAN_SubHandlerForMB.
  - Aligned watermark comparison logic between FLEXCAN_EnhancedRxFifoHandleIRQ and FLEXCAN_TransferReceiveEnhancedFifoNonBlocking for consistency.
  - Fixed Ehanced typo issue.
  - Remove redundant feature macro for FlexCAN engine clock selection in FLEXCAN_Init.
- Bug Fixes
  - Fixed Enhanced Rx FIFO filter configuration assertion idFilterPairNum in FLEXCAN_SetEnhancedRxFifoConfig.
  - Fixed Bus Off Done interrupt and Data Phase of Fast CAN FD Frames Error interrupt enable mask shift for CTRL2 register.
  - Fixed Enhanced Rx FIFO interrupt enable and status flag comparing issue in FLEXCAN_EnhancedRxFifoHandleIRQ.

[2.15.0]

- Improvements
  - Add remote request and response non-blocking transfer APIs.
    - FLEXCAN_TransferRemoteRequestNonBlocking
    - FLEXCAN_TransferRemoteResponseNonBlocking
- Bug Fixes
  - Fixed improper CS code when configuring FlexCAN Remote Response Message Buffer in FLEXCAN_SetRemoteResponseMbConfig.

[2.14.7]

- Improvements
  - Add Coverage Justification for uncovered code.
- Bug Fixes
  - Fixed violations of the CERT INT30-C INT31-C.

[2.14.6]

- Bug Fixes
  - Fixed MCR register reconfiguration failure after FlexCAN soft reset on some platforms.

[2.14.5]

- Improvements
  - Make API FLEXCAN_GetFDMailboxOffset public.
  - Add API FLEXCAN_SetMbID and FLEXCAN_SetFDMbID to configure Message Buffer ID individually.
- Bug Fixes
  - Fixed violations of the CERT INT30-C INT31-C.
  - Fixed violations of the CERT ARR30-C.

[2.14.4]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 8.4, 10.1, 10.4, 18.1.

[2.14.3]

- Improvements
  - Add unhandled interrupt events check for following API:
    - FLEXCAN_MbHandleIRQ
    - FLEXCAN_EhancedRxFifoHandleIRQ
- Bug Fixes
  - Remove FLEXCAN_MemoryErrorHandleIRQ on some platform without memory error interrupt.
  - Add conditional compile for CTRL2[ISOCANFDEN] because some platform do not have this bit.

[2.14.2]

- Improvements
  - Add Coverage Justification for uncovered code.
  - Adjust API FLEXCAN_TransferAbortReceive order.
  - Update FLEXCAN_Enable to enter Freeze Mode first when enter Disable mode on some platform.
  - Added while loop timeout for following API:
    - FLEXCAN_EnterFreezeMode
    - FLEXCAN_ExitFreezeMode
    - FLEXCAN_Enable
    - FLEXCAN_Reset
    - FLEXCAN_TransferSendBlocking

    * FLEXCAN_TransferReceiveBlocking
    * FLEXCAN_TransferFDSendBlocking
    * FLEXCAN_TransferFDReceiveBlocking
    * FLEXCAN_TransferReceiveFifoBlocking
    * FLEXCAN_TransferReceiveEnhancedFifoBlocking
- Bug Fixes
  - Remove remote frame feature in CANFD mode because there is no remote frame in the CANFD format.
  - Remove legacy Rx FIFO disabled branch in FLEXCAN_SubHandlerForLegacyRxFIFO and FLEXCAN_SubHandlerForDataTransfered.

[2.14.1]

- Bug Fixes
  - Fixed register IMASK2-4 IFLAG2-4 HR_TIME_STAMPn access issue on FlexCAN instances with different number of MBs.
  - Fixed bit field MBDSR1-3 access issue on FlexCAN instances with different number of MBs.
- Improvements
  - Unified following API as same parameter and return value type:
    * FLEXCAN_GetMbStatusFlags
    * FLEXCAN_ClearMbStatusFlags
    * FLEXCAN_EnableMbInterrupts
    * FLEXCAN_DisableMbInterrupts
  - Add workaround for ERR050443 and ERR052403.
  - Update message buffer read process in API FLEXCAN_ReadRxMb and FLEXCAN_ReadFDRxMb to make critical section as short as possible.
  - Simplify API FLEXCAN_DriverDataIRQHandler implementation by remove parameter type.

[2.14.0]

- Improvements
  - Support external time tick feature.
  - Support high resolution timestamp feature.
  - Enter Freeze Mode first when enter Disable Mode on some platform.
  - Add feature macro for Pretended Networking because some FlexCAN instance do not have this feature.
  - Add feature macro for enhanced Rx FIFO because some FlexCAN instance do not have this feature.
  - Add new FlexCAN IRQ Handler FLEXCAN_DriverDataIRQHandler and FLEXCAN_DriverEventIRQHandler. Thses IRQ Handlers are used on soc which FlexCAN interrupts are grouped by specific function and assigned to different vector.
  - Update macro FLEXCAN_WAKE_UP_FLAG and FLEXCAN_PNWAKE_UP_FLAG to simplify code.

  - Replace macro FSL_FEATURE_FLEXCAN_HAS_NO_WAKMSK_SUPPORT with FSL_FEATURE_FLEXCAN_HAS_NO_SLFWAK_SUPPORT.
  - Replace macro FSL_FEATURE_FLEXCAN_HAS_NO_WAKSRC_SUPPORT with FSL_FEATURE_FLEXCAN_HAS_GLITCH_FILTER.
- Bug Fixes
  - Fixed wrong interrupt and status flag helper macro in enumeration _flexcan_flags and API FLEXCAN_DisableInterrupts.
  - Fixed interrupt flag helper macro typo issue.
  - Remove flags which will are unassociated with interrupt in macro FLEXCAN_MEMORY_ERROR_INT_FLAG.
  - Remove flags which will are unassociated with interrupt in macro FLEXCAN_ERROR_AND_STATUS_INT_FLAG.
  - Fixed array out-of-bounds access when read enhanced Rx FIFO.

[2.13.1]

- Improvements
  - Conditionally compile interrupt handling code to solve the problem of using this driver on CPU cores that do not support interrupts.

[2.13.0]

- Improvements
  - Support payload endianness selection feature.

[2.12.0]

- Improvements
  - Support automatic Remote Response feature.
  - Add API FLEXCAN_SetRemoteResponseMbConfig() to configure automatic Remote Response mailbox.

[2.11.8]

- Improvements
  - Synchronize flexcan driver update on s32z platform.

[2.11.7]

- Bug Fixes
  - Fixed FLEXCAN_TransferReceiveEnhancedFifoEDMA() compatibility with edma5.

[2.11.6]

- Bug Fixes
  - Fixed ERRATA_9595 FLEXCAN_EnterFreezeMode() may result to bus fault on some platform.

[2.11.5]

- Bug Fixes
  - Fixed flexcan_memset() crash under high optimization compilation.

[2.11.4]

- Improvements
  - Update CANFD max bitrate to 10Mbps on MCXNx3x and MCXNx4x.
  - Release peripheral from reset if necessary in init function.

[2.11.3]

- Bug Fixes
  - Fixed FLEXCAN_TransferReceiveEnhancedFifoEDMA() compile error with DMA3.

[2.11.2]

- Bug Fixes
  - Fixed bug that timestamp in flexcan_handle_t not updated when RX overflow happens.

[2.11.1]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 10.1.

[2.11.0]

- Bug Fixes
  - Fixed wrong base address argument in FLEXCAN2 IRQ Handler.
- Improvements
  - Add API to determine if the instance supports CAN FD mode at run time.

[2.10.1]

- Bug Fixes
  - Fixed HIS CCM issue.
  - Fixed RTOS issue by adding protection to read-modify-write operations on interrupt enable/disable API.

[2.10.0]

- Improvements
  - Update driver to make it able to support devices which has more than 64 8bytes MBs.
  - Update CAN FD transfer APIs to make them set/get edl bit according to frame content, which can make them compatible with classic CAN.

[2.9.2]

- Bug Fixes
  - Fixed the issue that FLEXCAN_CheckUnhandleInterruptEvents() can't detecting the exist enhanced RX FIFO interrupt status.
  - Fixed the issue that FLEXCAN_ReadPNWakeUpMB() does not return fail even no existing valid wake-up frame.
  - Fixed the issue that FLEXCAN_ReadEnhancedRxFifo() may clear bits other than the data available bit.
  - Fixed violations of the MISRA C-2012 rules 10.4, 10.8.
- Improvements
  - Return kStatus_FLEXCAN_RxFifoDisabled instead of kStatus_Fail when read FIFO fail during IRQ handler.
  - Remove unreachable code from timing calculates APIs.
  - Update Enhanced Rx FIFO handler to make it deal with underflow/overflow status first.

[2.9.1]

- Bug Fixes
  - Fixed the issue that FLEXCAN_TransferReceiveEnhancedFifoBlocking() API clearing Fifo data available flag more than once.
  - Fixed the issue that entering FLEXCAN_SubHandlerForEhancedRxFifo() even if Enhanced Rx fifo interrupts are not enabled.
  - Fixed the issue that FLEXCAN_TransferReceiveEnhancedFifoEDMA() update handle even if previous Rx FIFO receive not finished.
  - Fixed the issue that FLEXCAN_SetEnhancedRxFifoConfig() not configure the ERFCR[NFE] bits to the correct value.
  - Fixed the issue that FLEXCAN_ReceiveFifoEDMACallback() can't differentiate between Rx fifo and enhanced rx fifo.
  - Fixed the issue that FLEXCAN_TransferHandleIRQ() can't report Legacy Rx FIFO warning status.

[2.9.0]

- Improvements
- Add public set bit rate API to make driver easier to use.
- Update Legacy Rx FIFO transfer APIs to make it support received multiple frames during one API call.
- Optimized FLEXCAN_SubHandlerForDataTransfered() API in interrupt handling to reduce the probability of packet loss.

[2.8.7]

- Improvements
- Initialized the EDMA configuration structure in the FLEXCAN EDMA driver.

[2.8.6]

- Bug Fixes
- Fix Coverity overrun issues in fsl_flexcan_edma driver.

[2.8.5]

- Improvements
  - Make driver aarch64 compatible.

[2.8.4]

- Bug Fixes
  - Fixed FlexCan_Errata_6032 to disable all interrupts.

[2.8.3]

- Bug Fixes
  - Fixed an issue with the FLEXCAN_EnableInterrupts and FLEXCAN_DisableInterrupts interrupt enable bits in the CTRL1 register.

[2.8.2]

- Bug Fixes
  - Fixed errors in timing calculations and simplify the calculation process.
  - Fixed issue of CBT and FDCBT register may write failure.

[2.8.1]

- Bug Fixes
  - Fixed the issue of CAN FD three sampling points.
  - Added macro to support the devices that no MCR[SUPV] bit.
  - Remove unnecessary clear WMB operations.

[2.8.0]

- Improvements
  - Update config configuration.
    - Added enableSupervisorMode member to support enable/disable Supervisor mode.
  - Simplified the algorithm in CAN FD improved timing APIs.

[2.7.1]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 10.3, 10.7.

[2.7.0]

- Improvements
  - Update config configuration.
    - Added enablePretendedeNetworking member to support enable/disable Pretended Networking feature.
    - Added enableTransceiverDelayMeasure member to support enable/disable Transceiver Delay MeasurementPretended feature.
    - Added bitRate/bitRateFD member to work as baudRate/baudRateFD member union.
  - Rename all “baud” in code or comments to “bit” to align with the CAN spec.
  - Added Pretended Networking mode related APIs.
    - FLEXCAN_SetPNConfig
    - FLEXCAN_GetPNMatchCount
    - FLEXCAN_ReadPNWakeUpMB
  - Added support for Enhanced Rx FIFO.
  - Removed independent memory error interrupt/status APIs and put all interrupt/status control operation into FLEXCAN_EnableInterrupts/FLEXCAN_DisableInterrupts and FLEXCAN_GetStatusFlags/FLEXCAN_ClearStatusFlags APIs.
  - Update improved timing APIs to make it calculate improved timing according to CiA doc recommended.
    - FLEXCAN_CalculateImprovedTimingValues.
    - FLEXCAN_FDCalculateImprovedTimingValues.
  - Update FLEXCAN_SetBitRate/FLEXCAN_SetFDBitRate to added the use of enhanced timing registers.

[2.6.2]

- Improvements
  - Add CANFD frame data length enumeration.

[2.6.1]

- Bug Fixes
  - Fixed the issue of not fully initializing memory in FLEXCAN_Reset() API.

[2.6.0]

- Improvements
  - Enable CANFD ISO mode in FLEXCAN_FDInit API.
  - Enable the transceiver delay compensation feature when enable FD operation and set bitrate switch.
  - Implementation memory error control in FLEXCAN_Init API.
  - Improve FLEXCAN_FDCalculateImprovedTimingValues API to get same value for FPRESDIV and PRESDIV.
  - Added memory error configuration for user.

        * enableMemoryErrorControl
        * enableNonCorrectableErrorEnterFreeze
    - Added memory error related APIs.
        * FLEXCAN_GetMemoryErrorReportStatus
        * FLEXCAN_GetMemoryErrorStatusFlags
        * FLEXCAN_ClearMemoryErrorStatusFlags
        * FLEXCAN_EnableMemoryErrorInterrupts
        * FLEXCAN_DisableMemoryErrorInterrupts
- Bug Fixes
    - Fixed the issue of sent duff CAN frame after call FLEXCAN_FDInit() API.

[2.5.2]

- Bug Fixes
    - Fixed the code error issue and simplified the algorithm in improved timing APIs.
        * The bit field in CTRL1 register couldn't calculate higher ideal SP, we set it as the lowest one(75%)
            · FLEXCAN_CalculateImprovedTimingValues
            · FLEXCAN_FDCalculateImprovedTimingValues
    - Fixed MISRA-C 2012 Rule 17.7 and 14.4.
- Improvements
    - Pass EsrStatus to callback function when kStatus_FLEXCAN_ErrorStatus is comming.

[2.5.1]

- Bug Fixes
    - Fixed the non-divisible case in improved timing APIs.
        * FLEXCAN_CalculateImprovedTimingValues
        * FLEXCAN_FDCalculateImprovedTimingValues

[2.5.0]

- Bug Fixes
    - MISRA C-2012 issue check.
        * Fixed rules, containing: rule-10.1, rule-10.3, rule-10.4, rule-10.7, rule-10.8, rule-11.8, rule-12.2, rule-13.4, rule-14.4, rule-15.5, rule-15.6, rule-15.7, rule-16.4, rule-17.3, rule-5.8, rule-8.3, rule-8.5.
    - Fixed the issue that API FLEXCAN_SetFDRxMbConfig lacks inactive message buff.
    - Fixed the issue of Pa082 warning.
    - Fixed the issue of dead lock in the function of interruption handler.
    - Fixed the issue of Legacy Rx Fifo EDMA transfer data fail in evkmimxrt1060 and evkmimxrt1064.
    - Fixed the issue of setting CANFD Bit Rate Switch.

  - Fixed the issue of operating unknown pointer risk.
    * when used the pointer “handle->mbFrameBuf[mbIdx]” to update the timestamp in a short-live TX frame, the frame pointer became as unknown, the action of operating it would result in program stack destroyed.
  - Added assert to check current CAN clock source affected by other clock gates in current device.
    * In some chips, CAN clock sources could be selected by CCM. But for some clock sources affected by other clock gates, if user insisted on using that clock source, they had to open these gates at the same time. However, they should take into consideration the power consumption issue at system level. In RT10xx chips, CAN clock source 2 was affected by the clock gate of lpuart1. ERRATA ID: (ERR050235 in CCM).

- Improvements
  - Implementation for new FLEXCAN with ECC feature able to exit Freeze mode.
  - Optimized the function of interruption handler.
  - Added two APIs for FLEXCAN EDMA driver.
    * FLEXCAN_PrepareTransfConfiguration
    * FLEXCAN_StartTransferDatafromRxFIFO
  - Added new API for FLEXCAN driver.
    * FLEXCAN_GetTimeStamp
      · For TX non-blocking API, we wrote the frame into mailbox only, so no need to register TX frame address to the pointer, and the timestamp could be updated into the new global variable handle->timestamp[mbIdx], the FLEXCAN driver provided a new API for user to get it by handle and index number after TX DONE Success.
    * FLEXCAN_EnterFreezeMode
    * FLEXCAN_ExitFreezeMode
  - Added new configuration for user.
    * disableSelfReception
    * enableListenOnlyMode
  - Renamed the two clock source enum macros based on CLKSRC bit field value directly.
    * The CLKSRC bit value had no property about Oscillator or Peripheral type in lots of devices, it acted as two different clock input source only, but the legacy enum macros name contained such property, that misled user to select incorrect CAN clock source.
  - Created two new enum macros for the FLEXCAN driver.
    * kFLEXCAN_ClkSrc0
    * kFLEXCAN_ClkSrc1
  - Deprecated two legacy enum macros for the FLEXCAN driver.
    * kFLEXCAN_ClkSrcOsc
    * kFLEXCAN_ClkSrcPeri
  - Changed the process flow for Remote request frame response..
    * Created a new enum macro for the FLEXCAN driver.
      · kStatus_FLEXCAN_RxRemote

  - Changed the process flow for kFLEXCAN_StateRxRemote state in the interrupt handler.
    * Should the TX frame not register to the pointer of frame handle, interrupt handler would not be able to read the remote response frame from the mail box to ram, so user should read the frame by manual from mail box after a complete remote frame transfer.

[2.4.0]

- Bug Fixes
  - MISRA C-2012 issue check.
    * Fixed rules, containing: rule-12.1, rule-17.7, rule-16.4, rule-11.9, rule-8.4, rule-14.4, rule-10.8, rule-10.4, rule-10.3, rule-10.7, rule-10.1, rule-11.6, rule-13.5, rule-11.3, rule-8.3, rule-12.2 and rule-16.1.
  - Fixed the issue that CANFD transfer data fail when bus baudrate is 30Khz.
  - Fixed the issue that ERR009595 does not folllow the ERRATA document.
  - Fixed code error for ERR006032 work around solution.
  - Fixed the Coverity issue of BAD_SHIFT in FLEXCAN.
  - Fixed the Repo build warning issue for variable without initial.
- Improvements
  - Fixed the run fail issue of FlexCAN RemoteRequest UT Case.
  - Implementation all TX and RX transfering Timestamp used in FlexCAN demos.
  - Fixed the issue of UT Test Fail for CANFD payload size changed from 64BperMB to 8PerMB.
  - Implementation for improved timing API by baud rate.

[2.3.2]

- Improvements
  - Implementation for ERR005959.
  - Implementation for ERR005829.
  - Implementation for ERR006032.

[2.3.1]

- Bug Fixes
  - Added correct handle when kStatus_FLEXCAN_TxSwitchToRx is comming.

[2.3.0]

- Improvements
  - Added self-wakeup support for STOP mode in the interrupt handling.

[2.2.3]

- Bug Fixes
  - Fixed the issue of CANFD data phase's bit rate not set as expected.

[2.2.2]

- Improvements
  - Added a time stamp feature and enable it in the interrupt_transfer example.

[2.2.1]

- Improvements
  - Separated CANFD initialization API.
  - In the interrupt handling, fix the issue that the user cannot use the normal CAN API when with an FD.

[2.2.0]

- Improvements
  - Added FSL_FEATURE_FLEXCAN_HAS_SUPPORT_ENGINE_CLK_SEL_REMOVE feature to support SoCs without CAN Engine Clock selection in FlexCAN module.
  - Added FlexCAN Serial Clock Operation to support i.MX SoCs.

[2.1.0]

- Bug Fixes
  - Corrected the spelling error in the function name FLEXCAN_XXX().
  - Moved Freeze Enable/Disable setting from FLEXCAN_Enter/ExitFreezeMode() to FLEXCAN_Init().
  - Corrected wrong helper macro values.
- Improvements
  - Hid FLEXCAN_Reset() from user.
  - Used NDEBUG macro to wrap FLEXCAN_IsMbOccupied() function instead of DEBUG macro.

[2.0.0]

- Initial version.

FLEXCAN_EDMA

[2.12.1]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 18.1.

[2.12.0]

- Improvements
  - Support high resolution timestamp feature in enhanced Rx FIFO EDMA.
  - Add feature macro for enhanced Rx FIFO because some FlexCAN instance do not have this feature.

- Bug Fixes
  - Fixed array out-of-bounds access when read enhanced Rx FIFO in EDMA.

[2.11.7]

- Refer FLEXCAN driver change log 2.7.0 to 2.11.7

FLEXIO

[2.3.2]

- Bug Fixes
  - Fixed MISRA 10.4 issues.

[2.3.1]

- New Features
  - Added common IRQ handler entry FLEXIO_CommonDriverIRQHandler.

[2.3.0]

- Improvements
  - Supported platforms which don't have DOZE mode control.
  - Added more pin control functions.

[2.2.3]

- Improvements
  - Adapter the FLEXIO driver to platforms which don't have system level interrupt controller, such as NVIC.

[2.2.2]

- Improvements
  - Release peripheral from reset if necessary in init function.

[2.2.1]

- Improvements
  - Added doxygen index parameter comment in FLEXIO_SetClockMode.

[2.2.0]

- New Features
  - Added new APIs to support FlexIO pin register.

[2.1.0]

- Improvements
  - Added API FLEXIO_SetClockMode to set flexio channel counter and source clock.

[2.0.4]

- Bug Fixes
  - Fixed MISRA 8.4 issues.

[2.0.3]

- Bug Fixes
  - Fixed MISRA 10.4 issues.

[2.0.2]

- Improvements
  - Split FLEXIO component which combines all flexio/flexio_uart/flexio_i2c/flexio_i2s drivers into several components: FlexIO component, flexio_uart component, flexio_i2c_master component, and flexio_i2s component.
- Bug Fixes
  - Fixed MISRA issues
    - Fixed rules 10.1, 10.3, 10.4, 10.7, 11.6, 11.9, 14.4, 17.7.

[2.0.1]

- Bug Fixes
  - Fixed the dozen mode configuration error in FLEXIO_Init API. For enableInDoze = true, the configuration should be 0; for enableInDoze = false, the configuration should be 1.

FLEXIO_A-FORMAT

[1.0.0]

- New Features
  - The polling mode was added to read or configure encoder data
  - The interrupt mode was added to read or configure encoder data

FLEXIO_CAMERA

[2.2.1]

- Bug Fixes
  - Fixed INT30-C INT31-C issues.
  - Set SHIFTCFG[LATST]=1 on devices where the bit is available, so each shifter stores its post-shift state and captures the final byte of the chain.

[2.2.0]

- Improvements
  - Supported platforms which don't have DOZE mode control.

[2.1.3]

- Bug Fixes
  - Fixed MISRA 10.4 issues.

[2.1.2]

- Improvements
  - Unified component full name to FLEXIO CAMERA (EDMA) driver.
- Bug Fixes
  - Fixed MISRA issues
    - Fixed rules 10.1, 10.3, 10.4, 10.7, 11.6, 11.9, 14.4, 17.7.

[2.1.1]

- Bug Fixes
  - The following modifications support FlexIO using multiple instances:
    - Removed FLEXIO_Reset API in module Init APIs.
    - Updated module Deinit APIs to reset the shifter/timer configuration instead of disabling module and clock.
    - Updated module Enable APIs to only support enable operation.

[2.1.0]

- New Features
  - Added Transfer prefix in transactional APIs.

FLEXIO_I2C

[2.6.3]

- Bug Fixes
  - Fixed MISRA 10.4, 10.7 and 14.4 issues.

[2.6.2]

- Improvements
  - Added timeout for while loop in FLEXIO_I2C_MasterTransferBlocking().
- Bug Fixes
  - Fixed build issues related to I2C_RETRY_TIMES.

[2.6.1]

- Bug Fixes
  - Fixed coverity issues

[2.6.0]

- Improvements
  - Supported platforms which don't have DOZE mode control.

[2.5.1]

- Improvements
  - Conditionally compile interrupt handling code to solve the problem of using this driver on CPU cores that do not support interrupts.

[2.5.0]

- Improvements
  - Split some functions, fixed CCM problem in file fsl_flexio_i2c_master.c.

[2.4.0]

- Improvements
  - Added delay of 1 clock cycle in FLEXIO_I2C_MasterTransferRunStateMachine to ensure that bus would be idle before next transfer if master is nacked.
  - Fixed issue that the restart setup time is less than the time in I2C spec by adding delay of 1 clock cycle before restart signal.

[2.3.0]

- Improvements
  - Used 3 timers instead of 2 to support transfer which is more than 14 bytes in single transfer.
  - Improved FLEXIO_I2C_MasterTransferGetCount so that the API can check whether the transfer is still in progress.
- Bug Fixes
  - Fixed MISRA 10.4 issues.

[2.2.0]

- New Features
  - Added timeout mechanism when waiting certain state in transfer API.
  - Added an API for checking bus pin status.
- Bug Fixes
  - Fixed COVERITY issue of useless call in FLEXIO_I2C_MasterTransferRunStateMachine.
  - Fixed MISRA issues
    - Fixed rules 10.1, 10.3, 10.4, 10.7, 11.6, 11.9, 14.4, 17.7.

  - Added codes in FLEXIO_I2C_MasterTransferCreateHandle to clear pending NVIC IRQ, disable internal IRQs before enabling NVIC IRQ.
  - Modified code so that during master's nonblocking transfer the start and slave address are sent after interrupts being enabled, in order to avoid potential issue of sending the start and slave address twice.

[2.1.7]

- Bug Fixes
  - Fixed the issue that FLEXIO_I2C_MasterTransferBlocking did not wait for STOP bit sent.
  - Fixed COVERITY issue of useless call in FLEXIO_I2C_MasterTransferRunStateMachine.
  - Fixed the issue that I2C master did not check whether bus was busy before transfer.

[2.1.6]

- Bug Fixes
  - Fixed the issue that I2C Master transfer APIs(blocking/non-blocking) did not support the situation of master transfer with subaddress and transfer data size being zero, which means no data followed the subaddress.

[2.1.5]

- Improvements
  - Unified component full name to FLEXIO I2C Driver.

[2.1.4]

- Bug Fixes
  - The following modifications support FlexIO using multiple instances:
    * Removed FLEXIO_Reset API in module Init APIs.
    * Updated module Deinit APIs to reset the shifter/timer config instead of disabling module/clock.
    * Updated module Enable APIs to only support enable operation.

[2.1.3]

- Improvements
  - Changed the prototype of FLEXIO_I2C_MasterInit to return kStatus_Success if initialized successfully or to return kStatus_InvalidArgument if "(srcClock_Hz / masterConfig->baudRate_Bps) / 2 - 1" exceeds 0xFFU.

[2.1.2]

- Bug Fixes
  - Fixed the FLEXIO I2C issue where the master could not receive data from I2C slave in high baudrate.
  - Fixed the FLEXIO I2C issue where the master could not receive NAK when master sent non-existent addr.

  - Fixed the FLEXIO I2C issue where the master could not get transfer count successfully.
  - Fixed the FLEXIO I2C issue where the master could not receive data successfully when sending data first.
  - Fixed the Dozen mode configuration error in FLEXIO_I2C_MasterInit API. For enableInDoze = true, the configuration should be 0; for enableInDoze = false, the configuration should be 1.
  - Fixed the issue that FLEXIO_I2C_MasterTransferBlocking API called FLEXIO_I2C_MasterTransferCreateHandle, which lead to the s_flexioHandle/s_flexioIsr/s_flexioType variable being written. Then, if calling FLEXIO_I2C_MasterTransferBlocking API multiple times, the s_flexioHandle/s_flexioIsr/s_flexioType variable would not be written any more due to it being out of range. This lead to the following situation: NonBlocking transfer APIs could not work due to the fail of register IRQ.

[2.1.1]

- Bug Fixes
  - Implemented the FLEXIO_I2C_MasterTransferBlocking API which is defined in header file but has no implementation in the C file.

[2.1.0]

- New Features
  - Added Transfer prefix in transactional APIs.
  - Added transferSize in handle structure to record the transfer size.

FLEXIO_I2S

[2.2.2]

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 12.4.

[2.2.1]

- Improvements
  - Conditionally compile interrupt handling code to solve the problem of using this driver on CPU cores that do not support interrupts.

[2.2.0]

- New Features
  - Added timeout mechanism when waiting certain state in transfer API.
- Bug Fixes
  - Fixed IAR Pa082 warnings.
  - Fixed violations of the MISRA C-2012 rules 10.4, 14.4, 11.8, 11.9, 10.1, 17.7, 11.6, 10.3, 10.7.

[2.1.6]

- Bug Fixes
  - Added reset flexio before flexio i2s init to make sure flexio status is normal.

[2.1.5]

- Bug Fixes
  - Fixed the issue that I2S driver used hard code for bitwidth setting.

[2.1.4]

- Improvements
  - Unified component's full name to FLEXIO I2S (DMA/EDMA) driver.

[2.1.3]

- Bug Fixes
  - The following modifications support FLEXIO using multiple instances:
    - Removed FLEXIO_Reset API in module Init APIs.
    - Updated module Deinit APIs to reset the shifter/timer config instead of disabling module/clock.
    - Updated module Enable APIs to only support enable operation.

[2.1.2]

- New Features
  - Added configure items for all pin polarity and data valid polarity.
  - Added default configure for pin polarity and data valid polarity.

[2.1.1]

- Bug Fixes
  - Fixed FlexIO I2S RX data read error and eDMA address error.
  - Fixed FlexIO I2S slave timer compare setting error.

[2.1.0]

- New Features
  - Added Transfer prefix in transactional APIs.
  - Added transferSize in handle structure to record the transfer size.

FLEXIO_I2S_EDMA

[2.1.9]

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 12.4.

[2.1.8]

- Improvements
  - Applied EDMA ERRATA 51327.

FLEXIO_MCU_LCD

[2.3.0]

- New Features
  - Supported passing an extra user defined parameter to GPIO functions to control the CS/RS/RDWR pin signal.

[2.2.0]

- Improvements
  - Supported platforms which don't have DOZE mode control.

[2.1.0]

- New Features
  - Supported transmit only data without command.

[2.0.8]

- Bug Fixes
  - Fixed bug that FLEXIO_MCULCD_Init return kStatus_Success even with invalid parameter.
  - Fixed glitch on WR, that when initially configure the timer pin as output, or change the pin back to disabled, the pin may be driven low causing glitch on bus. Configure the pin as bidirection output first then perform a subsequent write to change to output or dsiabled to avoid the issue.

[2.0.6]

- Bug Fixes
  - Fixed MISRA 10.4 issues when FLEXIO_MCULCD_DATA_BUS_WIDTH defined as signed value.

[2.0.5]

- Improvements
  - Changed FLEXIO_MCULCD_WriteDataArrayBlocking's data parameter to const type.

[2.0.4]

- Bug Fixes
  - Fixed MISRA 10.4 issues.

[2.0.3]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 10.1, 10.3, 10.4, 10.6, 14.4, 17.7.

[2.0.2]

- Improvements
  - Unified component full name to FLEXIO_MCU_LCD (EDMA) driver.

[2.0.1]

- Bug Fixes
  - The following modification to support FlexIO using multiple instances:
    - Removed FLEXIO_Reset API in module Init APIs.
    - Updated module Deinit APIs to reset the shifter/timer configuration instead of disabling module and clock.
    - Updated module Enable APIs to only support enable operation.

[2.0.0]

- Initial version.

FLEXIO_MCU_LCD_EDMA

[2.0.6]

- New Features
  - Supported passing an extra user defined parameter to GPIO functions to control the RDWR pin signal.

[2.0.5]

- New Features
  - Supported transmit only data without command.

[2.0.4]

- Bug Fixes
  - Fixed MISRA 10.4 issues.

[2.0.3]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 10.1, 10.3, 10.4, 10.6, 14.4, 17.7.

[2.0.2]

- Improvements
  - Unified component full name to FLEXIO_MCU_LCD (EDMA) driver.

[2.0.1]

- Bug Fixes
  - The following modification to support FlexIO using multiple instances:
    - Removed FLEXIO_Reset API in module Init APIs.
    - Updated module Deinit APIs to reset the shifter/timer configuration instead of disabling module and clock.
    - Updated module Enable APIs to only support enable operation.

[2.0.0]

- Initial version.

FLEXIO_MCU_LCD_SMARTDMA

[2.0.7]

- Other Changes
  - Add more MCXA devices support.

[2.0.6]

- Other Changes
  - Add more MCXA devices support.

[2.0.5]

- Other Changes
  - Supported the MCXA platforms.
- New Features
  - Supported passing an extra user defined parameter to GPIO functions to control the RDWR pin signal.

[2.0.4]

- New Features
  - Supported the platforms which use FlexIO SHIFTER DMA to trigger SmartDMA, such as MCXN235, MCXN236.

[2.0.3]

- New Features
  - Supported transmit only data without command.

[2.0.2]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 10.1, 10.3, 10.4, 10.6, 14.4, 17.7.

[2.0.1]

- Other Changes
  - Update driver implementation due to SMARTDMA driver update.

[2.0.0]

- Initial version.

FLEXIO_SPI

[2.4.4]

- Bug Fixes
  - Fixed MISRA 10.4 issues.

[2.4.3]

- Improvements
  - Make SPI_RETRY_TIMES configurable by CONFIG_SPI_RETRY_TIMES.

[2.4.2]

- Bug Fixes
  - Fixed FLEXIO_SPI_MasterTransferBlocking and FLEXIO_SPI_MasterTransferNonBlocking issue in CS continuous mode, the CS might not be continuous.

[2.4.1]

- Bug Fixes
  - Fixed coverity issues

[2.4.0]

- Improvements
  - Supported platforms which don't have DOZE mode control.

[2.3.5]

- Improvements
  - Conditionally compile interrupt handling code to solve the problem of using this driver on CPU cores that do not support interrupts.

[2.3.4]

- Bug Fixes
  - Fixed the txData from void * to const void * in transmit API

[2.3.3]

- Bugfixes
  - Fixed cs-continuous mode.

[2.3.2]

- Improvements
  - Changed FLEXIO_SPI_DUMMYDATA to 0x00.

[2.3.1]

- Bugfixes
  - Fixed IRQ SHIFTBUF overrun issue when one FLEXIO instance used as multiple SPIs.

[2.3.0]

- New Features
  - Supported FLEXIO_SPI slave transfer with continuous master CS signal and CPHA=0.
  - Supported FLEXIO_SPI master transfer with continuous CS signal.
  - Support 32 bit transfer width.
- Bug Fixes
  - Fixed wrong timer compare configuration for dma/edma transfer.
  - Fixed wrong byte order of rx data if transfer width is 16 bit, since the we use shifter buffer bit swapped/byte swapped register to read in received data, so the high byte should be read from the high bits of the register when MSB.

[2.2.1]

- Bug Fixes
  - Fixed bug in FLEXIO_SPI_MasterTransferAbortEDMA that when aborting EDMA transfer EDMA_AbortTransfer should be used rather than EDMA_StopTransfer.

[2.2.0]

- Improvements
  - Added timeout mechanism when waiting certain states in transfer driver.
- Bug Fixes
  - Fixed MISRA 10.4 issues.
  - Added codes in FLEXIO_SPI_MasterTransferCreateHandle and FLEXIO_SPI_SlaveTransferCreateHandle to clear pending NVIC IRQ before enabling NVIC IRQ, to fix issue of pending IRQ interfering the on-going process.

[2.1.3]

- Improvements
  - Unified component full name to FLEXIO SPI(DMA/EDMA) Driver.
- Bug Fixes
  - Fixed MISRA issues
    - Fixed rules 10.1, 10.3, 10.4, 10.7, 11.6, 11.9, 14.4, 17.7.

[2.1.2]

- Bug Fixes
  - The following modification support FlexIO using multiple instances:
    - Removed FLEXIO_Reset API in module Init APIs.
    - Updated module Deinit APIs to reset the shifter/timer config instead of disabling module/clock.
    - Updated module Enable APIs to only support enable operation.

[2.1.1]

- Bug Fixes
  - Fixed bug where FLEXIO SPI transfer data is in 16 bit per frame mode with eDMA.
  - Fixed bug when FLEXIO SPI works in eDMA and interrupt mode with 16-bit per frame and Lsbfirst.
  - Fixed the Dozen mode configuration error in FLEXIO_SPI_MasterInit/FLEXIO_SPI_SlaveInit API. For enableInDoze = true, the configuration should be 0; for enableInDoze = false, the configuration should be 1.
- Improvements
  - Added #ifndef/#endif to allow users to change the default TX value at compile time.

[2.1.0]

- New Features
  - Added Transfer prefix in transactional APIs.
  - Added transferSize in handle structure to record the transfer size.
- Bug Fixes
  - Fixed the error register address return for 16-bit data write in FLEXIO_SPI_GetTxDataRegisterAddress.
  - Provided independent IRQHandler/transfer APIs for Master and slave to fix the baudrate limit issue.

FLEXIO_T-FORMAT

[1.0.0]

- New Features
  - The polling mode was added to read or configure encoder data
  - The interrupt mode was added to read or configure encoder data

FLEXIO_UART

[2.6.5]

- Bug Fixes
  - Fixed MISRA 10.4 issues.

[2.6.4]

- Improvements
  - Make UART_RETRY_TIMES configurable by CONFIG_UART_RETRY_TIMES.

[2.6.3]

- Bug Fixes
  - Fixed coverity issues

[2.6.2]

- Bug Fixes
  - Fixed coverity issues

[2.6.1]

- Improvements
  - Improve baudrate calculation method, to support higher frequency FlexIO clock source.

[2.6.0]

- Improvements
  - Supported platforms which don't have DOZE mode control.

[2.5.1]

- Improvements
  - Conditionally compile interrupt handling code to solve the problem of using this driver on CPU cores that do not support interrupts.

[2.5.0]

- Improvements
  - Added API FLEXIO_UART_FlushShifters to flush UART fifo.

[2.4.0]

- Improvements
  - Use separate data for TX and RX in flexio_uart_transfer_t.
- Bug Fixes
  - Fixed bug that when ring buffer is used, if some data is received in ring buffer first before calling FLEXIO_UART_TransferReceiveNonBlocking, the received data count returned by FLEXIO_UART_TransferGetReceiveCount is wrong.

[2.3.0]

- Improvements
  - Added check for baud rate's accuracy that returns kStatus_FLEXIO_UART_BaudrateNotSupport when the best achieved baud rate is not within 3% error of configured baud rate.
- Bug Fixes
  - Added codes in FLEXIO_UART_TransferCreateHandle to clear pending NVIC IRQ before enabling NVIC IRQ, to fix issue of pending IRQ interfering the on-going process.

[2.2.0]

- Improvements
  - Added timeout mechanism when waiting for certain states in transfer driver.
- Bug Fixes
  - Fixed MISRA 10.4 issues.

[2.1.6]

- Bug Fixes
  - Fixed IAR Pa082 warnings.
  - Fixed MISRA issues
    - Fixed rules 10.1, 10.3, 10.4, 10.7, 11.6, 11.9, 14.4, 17.7.

[2.1.5]

- Improvements
  - Triggered user callback after all the data in ringbuffer were received in FLEXIO_UART_TransferReceiveNonBlocking.

[2.1.4]

- Improvements
  - Unified component full name to FLEXIO UART(DMA/EDMA) Driver.

[2.1.3]

- Bug Fixes
  - The following modifications support FLEXIO using multiple instances:
    * Removed FLEXIO_Reset API in module Init APIs.
    * Updated module Deinit APIs to reset the shifter/timer configuration instead of disabling module and clock.
    * Updated module Enable APIs to only support enable operation.

[2.1.2]

- Bug Fixes
  - Fixed the transfer count calculation issue in FLEXIO_UART_TransferGetReceiveCount, FLEXIO_UART_TransferGetSendCount, FLEXIO_UART_TransferGetReceiveCountDMA, FLEXIO_UART_TransferGetSendCountDMA, FLEXIO_UART_TransferGetReceiveCountEDMA and FLEXIO_UART_TransferGetSendCountEDMA.
  - Fixed the Dozen mode configuration error in FLEXIO_UART_Init API. For enableInDoze = true, the configuration should be 0; for enableInDoze = false, the configuration should be 1.
  - Added code to report errors if the user sets a too-low-baudrate which FLEXIO cannot reach.
  - Disabled FLEXIO_UART receive interrupt instead of all NVICs when reading data from ring buffer. If ring buffer is used, receive nonblocking will disable all NVIC interrupts to protect the ring buffer. This had negative effects on other IPs using interrupt.

[2.1.1]

- Bug Fixes
  - Changed the API name FLEXIO_UART_StopRingBuffer to FLEXIO_UART_TransferStopRingBuffer to align with the definition in C file.

[2.1.0]

- New Features
  - Added Transfer prefix in transactional APIs.
  - Added txSize/rxSize in handle structure to record the transfer size.
- Bug Fixes
  - Added an error handle to handle the situation that data count is zero or data buffer is NULL.

FLEXIO_UART_EDMA

[2.3.1]

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

[2.3.0]

- Refer FLEXIO_UART driver change log to 2.3.0

FlexPWM

[2.0.0]

- Initial version of FlexPWM driver which is refactored from PWM driver (fsl_pwm.c/h).
- Improvements
  - Decomposed monolithic initialization into 11 dedicated configuration functions following single responsibility principle.
    - FLEXPWM_ConfigSubmodule for counter and reload configuration.
    - FLEXPWM_ConfigPWM for PWM output configuration.
    - FLEXPWM_ConfigPWMChannelX for PWM_X channel configuration.
    - FLEXPWM_ConfigFaultProtection for fault protection settings.
    - FLEXPWM_ConfigInputCapture for input capture configuration.
    - FLEXPWM_ConfigOutputTrigger for output trigger configuration.
    - FLEXPWM_ConfigDMAControl for DMA control settings.
    - And other specialized configuration functions.
  - Added inline register access APIs for zero-overhead direct control.
    - FLEXPWM_SetVAL0 through FLEXPWM_SetVAL5 compile to single-instruction register writes.
  - Reorganized data structures into hierarchical configuration for better clarity.
    - flexpwm_submodule_config_t for submodule-level settings.
    - flexpwm_pwm_config_t for PWM signal parameters.
    - flexpwm_fault_protection_config_t for fault protection.
  - Added atomic multi-submodule control using bitmask-based operations.
    - FLEXPWM_EnableSubmoduleCounter supports simultaneous start of multiple submodules.
    - Eliminates race conditions in multi-channel scenarios.
  - Improved fault protection configuration with dedicated structures and APIs.
  - Updated naming convention from PWM_* to FLEXPWM_* to align with peripheral name.
  - Removed implicit side effects from initialization functions for more predictable behavior.

FREQME

[2.2.0]

- Improvements
  - Add following API to support FREQME which exposes dedicated REF and TAR registers for clock source selection.
    - FREQME_SetReferenceClk

    * FREQME_SetTargetClk
  - Support some devices which apply a different frequency measurement formula (result + 1 instead of result - 2).

[2.1.4]

- Improvements
  - Clarified pulse width measurement mode usage.

[2.1.3]

- Bug Fixes
  - Fixed violations of the CERT INT30-C INT31-C.

[2.1.2]

- Improvements
  - Release peripheral from reset if necessary in init function.

[2.1.1]

- Fixed MISRA issues.

[2.1.0]

- Updated register name.

[2.0.0]

- Initial version.

GLIKEY

[2.0.1]

- Implement INIT state recovery from the LOCKED state after a reset when the previous index was locked.

[2.0.0]

- Initial version.

GPIO

[2.8.6]

- Bug Fixes
  - Fixed CERT INT31-C violations in GPIO_FIT_REG macro for platforms with 8-bit register width.

[2.8.5]

- Improvements
  - Add AND logic in GPIO_GpioClearInterruptFlags to support clearing multiple interrupt flags simultaneously.

[2.8.4]

- Improvements
  - Make function GPIO_PortGetInterruptFlags and GPIO_PortClearInterruptFlags available for all variants, they are used for all pins flags in one GPIO port.

[2.8.3]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 Rule 10.1, 5.7.

[2.8.2]

- Bug Fixes
  - Fixed COVERITY issue that GPIO_GetInstance could return clock array overflow values due to GPIO base and clock being out of sync.

[2.8.1]

- Bug Fixes
  - Fixed CERT INT31-C issues.

[2.8.0]

- Improvements
  - Add API GPIO_PortInit/GPIO_PortDeinit to set GPIO clock enable and releasing GPIO reset.

[2.8.0]

- Improvements
  - Add API GPIO_PortInit/GPIO_PortDeinit to set GPIO clock enable and releasing GPIO reset.
  - Remove support for API GPIO_GetPinsDMARequestFlags with GPIO_ISFR_COUNT <= 1.

[2.7.3]

- Improvements
  - Release peripheral from reset if necessary in init function.

[2.7.2]

- New Features
  - Support devices without PORT module.

[2.7.1]

- Bug Fixes
  - Fixed MISRA C-2012 rule 10.4 issues in GPIO_GpioGetInterruptChannelFlags() function and GPIO_GpioClearInterruptChannelFlags() function.

[2.7.0]

- New Features
  - Added API to support Interrupt select (IRQS) bitfield.

[2.6.0]

- New Features
  - Added API to get GPIO version information.
  - Added API to control a pin for general purpose input.
  - Added some APIs to control pin in secure and previliege status.

[2.5.3]

- Bug Fixes
  - Correct the feature macro typo: FSL_FEATURE_GPIO_HAS_NO_INDEP_OUTPUT_CONTORL.

[2.5.2]

- Improvements
  - Improved GPIO_PortSet/GPIO_PortClear/GPIO_PortToggle functions to support devices without Set/Clear/Toggle registers.

[2.5.1]

- Bug Fixes
  - Fixed wrong macro definition.
  - Fixed MISRA C-2012 rule issues in the FGPIO_CheckAttributeBytes() function.
  - Defined the new macro to separate the scene when the width of registers is different.
  - Removed some redundant macros.
- New Features
  - Added some APIs to get/clear the interrupt status flag when the port doesn't control pins' interrupt.

[2.4.1]

- Improvements
  - Improved GPIO_CheckAttributeBytes() function to support 8 bits width GACR register.

[2.4.0]

- Improvements
  - API interface added:
    * New APIs were added to configure the GPIO interrupt clear settings.

[2.3.2]

- Bug Fixes
  - Fixed the issue for MISRA-2012 check.
    * Fixed rule 3.1, 10.1, 8.6, 10.6, and 10.3.

[2.3.1]

- Improvements
  - Removed deprecated APIs.

[2.3.0]

- New Features
  - Updated the driver code to adapt the case of interrupt configurations in GPIO module. New APIs were added to configure the GPIO interrupt settings if the module has this feature on it.

[2.2.1]

- Improvements
  - API interface changes:
    * Refined naming of APIs while keeping all original APIs by marking them as deprecated. The original APIs will be removed in next release. The main change is updating APIs with prefix of _PinXXX() and _PortXXX.

[2.1.1]

- Improvements
  - API interface changes:
    * Added an API for the check attribute bytes.

[2.1.0]

- Improvements
  - API interface changes:
    * Added “pins” or “pin” to some APIs’ names.
    * Renamed “_PinConfigure” to “GPIO_PinInit”.

I3C

[2.15.0]

- Improvements
  - Added new timing APIs (I3C_MasterCalcTiming, I3C_MasterSetTiming) and supporting types to provide bus-topology-aware baud rate calculation with ODHPP control and pre-computed timing switching.
- New Features
  - Added I3C_MasterGetI2CPresetTiming to get baud rate settings which meet I2C timing.
- Bug Fixes
  - Fixed Coverity issues.

[2.14.7]

- Bug Fixes
  - Fixed I3C master interrupt transfer not stopping the bus on errors other than Nak/IBIWon.

[2.14.6]

- New Features
  - Added common IRQ handler entry I3C_DriverIRQHandler.

[2.14.5]

- Bug Fixes
  - Fixed CERT INT31-C violation: cast bool field enableSlave to uint via ternary in I3C_Init.

[2.14.4]

- Improvements
  - Fixed MSG violations.

[2.14.3]

- Improvements
  - Fixed Coverity CERT-C violations.
  - Used I3C_RSTS instead of I3C special feature macro.
  - Adapted the driver to support new platform.

[2.14.2]

- Improvements
  - Added timeout for ENTDAA process API.
  - Added build system macro to control the timeout setting.

[2.14.1]

- Improvements
  - Split the function I3C_MasterTransferBlocking to meet the HIS-CCM requirement.

[2.14.0]

- Improvements
  - Added the choice to set fast start header with push-pull speed when all targets addresses have MSB 0 instead of forcing to set it.
  - Deleted duplicated busy check in I3C_MasterStart function.

[2.13.1]

- Bug Fixes
  - Disabled Rx auto-termination in repeated start interrupt event while transfer API doesn't enable it.
  - Waited the completion event after loading all Tx data in Tx FIFO.
- Improvements
  - Conditionally compile interrupt handling code to solve the problem of using this driver on CPU cores that do not support interrupts.

[2.13.0]

- New features
  - Added the hot-join support for I3C bus initialization API.
- Bug Fixes
  - Set read termination with START at the same time in case unknown issue.
  - Set MCTRL[TYPE] as 0 for DDR force exit.
- Improvements
  - Added the API to reset device count assigned by ENTDAA.
  - Provided the method to set global macro I3C_MAX_DEVCNT to determine how many device addresses ENTDAA can allocate at one time.
  - Initialized target management static array based on instance number for the case that multiple instances are used at the same time.

[2.12.0]

- Improvements
  - Added the slow clock parameter for Controller initialization function to calculate accurate timeout.
- Bug Fixes
  - Fixed the issue that BAMATCH field can't be 0. BAMATCH should be 1 for 1MHz slow clock.

[2.11.1]

- Bug Fixes
  - Fixed the issue that interrupt API transmits extra byte when subaddress and data size are null.
  - Fixed the slow clock calculation issue.

[2.11.0]

- New features
  - Added the START/ReSTART SCL delay setting for the Soc which supports this feature.
- Bug Fixes
  - Fixed the issue that ENTDAA process waits Rx pending flag which causes problem when Rx watermark isn't 0. Just check the Rx FIFO count.

[2.10.8]

- Improvements
  - Support more instances.

[2.10.7]

- Improvements
  - Fixed the potential compile warning.

[2.10.6]

- New features
  - Added the I3C private read/write with 0x7E address as start.

[2.10.5]

- New features
  - Added I3C HDR-DDR transfer support.

[2.10.4]

- Improvements
  - Added one more option for master to not set RDTERM when doing I3C Common Command Code transfer.

[2.10.3]

- Improvements
  - Masked the slave IBI/MR/HJ request functions with feature macro.

[2.10.2]

- Bug Fixes
  - Added workaround for errata ERR051617: I3C working with I2C mode creates the unintended Repeated START before actual STOP on some platforms.

[2.10.1]

- Bug Fixes
  - Fixed the issue that DAA function doesn't wait until all Rx data is read out from FIFO after master control done flag is set.
  - Fixed the issue that DAA function could return directly although the disabled interrupts are not enabled back.

[2.10.0]

- New features
  - Added I3C extended IBI data support.

[2.9.0]

- Improvements
  - Added adaptive termination for master blocking transfer. Set termination with start signal when receiving bytes less than 256.

[2.8.2]

- Improvements
  - Fixed the build warning due to armgcc strict check.

[2.8.1]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 17.7.

[2.8.0]

- Improvements
  - Added API I3C_MasterProcessDAASpecifiedBaudrate for temporary baud rate adjustment when I3C master assigns dynamic address.

[2.7.1]

- Bug Fixes
  - Fixed the issue that I3C slave handle STOP event before finishing data transmission.

[2.7.0]

- Fixed the CCM problem in file fsl_i3c.c.
- Fixed the FSL_FEATURE_I3C_HAS_NO_SCONFIG_IDRAND usage issue in I3C_GetDefaultConfig and I3C_Init.

[2.6.0]

- Fixed the FSL_FEATURE_I3C_HAS_NO_SCONFIG_IDRAND usage issue in fsl_i3c.h.
- Changed some static functions in fsl_i3c.c as non-static and define the functions in fsl_i3c.h to make I3C DMA driver reuse:
  - I3C_GetIBIType
  - I3C_GetIBIAddress
  - I3C_SlaveCheckAndClearError
- Changed the handle pointer parameter in IRQ related funtions to void * type to make it reuse in I3C DMA driver.
- Added new API I3C_SlaveRequestIBIWithSingleData for slave to request single data byte, this API could be used regardless slave is working in non-blocking interrupt or non-blocking dma.
- Added new API I3C_MasterGetDeviceListAfterDAA for master application to get the device information list built up in DAA process.

[2.5.4]

- Improved I3C driver to avoid setting state twice in the SendCommandState of I3C_RunTransferStateMachine.
- Fixed MISRA violation of rule 20.9.
- Fixed the issue that I3C_MasterEmitRequest did not use Type I3C SDR.

[2.5.3]

- Updated driver for new feature FSL_FEATURE_I3C_HAS_NO_SCONFIG_BAMATCH and FSL_FEATURE_I3C_HAS_NO_SCONFIG_IDRAND.

[2.5.2]

- Updated driver for new feature FSL_FEATURE_I3C_HAS_NO_MERRWARN_TERM.
- Fixed the issue that call to I3C_MasterTransferBlocking API did not generate STOP signal when NAK status was returned.

[2.5.1]

- Improved the receive terminate size setting for interrupt transfer read, now it's set at beginning of transfer if the receive size is less than 256 bytes.

[2.5.0]

- Added new API I3C_MasterRepeatedStartWithRxSize to send repeated start signal with receive terminate size specified.
- Fixed the status used in I3C_RunTransferStateMachine, changed to use pending interrupts as status to be handled in the state machine.
- Fixed MISRA 2012 violation of rule 10.3, 10.7.

[2.4.0]

- Bug Fixes
  - Fixed kI3C_SlaveMatchedFlag interrupt is not properly handled in I3C_SlaveTransferHandleIRQ when it comes together with interrupt kI3C_SlaveBusStartFlag.
  - Fixed the inaccurate I2C baudrate calculation in I3C_MasterSetBaudRate.
  - Added new API I3C_MasterGetIBIRules to get registered IBI rules.
  - Added new variable isReadTerm in struct _i3c_master_handle for transfer state routine to check if MCTRL.RDTERM is configured for read transfer.
  - Changed to emit Auto IBI in transfer state routine for slave start flag assertion.
  - Fixed the slave maxWriteLength and maxReadLength does not be configured into SMAXLIMITS register issue.
  - Fixed incorrect state for IBI in I3C master interrupt transfer IRQ handle routine.
  - Added isHotJoin in i3c_slave_config_t to request hot-join event during slave init.

[2.3.2]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 8.4, 17.7.
  - Fixed incorrect HotJoin event index in I3C_GetIBIType.

[2.3.1]

- Bug Fixes
  - Fixed the issue that call of I3C_MasterTransferBlocking/I3C_MasterTransferNonBlocking fails for the case which receive length 1 byte of data.
  - Fixed the issue that STOP signal is not sent when NAK status is detected during execution of I3C_MasterTransferBlocking function.

[2.3.0]

- Improvements
  - Added I3C common driver APIs to initialize I3C with both master and slave configuration.
  - Updated I3C master transfer callback to function set structure to include callback invoke for IBI event and slave2master event.
  - Updated I3C master non-blocking transfer model and always enable the interrupts to be able to re-act to the slave start event and handle slave IBI.

[2.2.0]

- Bug Fixes
  - Fixed the issue that I3C transfer size limit to 255 bytes.

[2.1.2]

- Bug Fixes
  - Reset default hkeep value to kI3C_MasterHighKeeperNone in I3C_MasterGetDefaultConfig

[2.1.1]

- Bug Fixes
  - Fixed incorrect FIFO reset operation in I3C Master Transfer APIs.
  - Fixed i3c slave IRQ handler issue, slave transmit could be underrun because tx FIFO is not filled in time right after start flag detected.

[2.1.0]

- Added definitions and APIs for I3C slave functionality, updated previous I3C APIs to support I3C functionality.

[2.0.0]

- Initial version.

I3C_EDMA

[2.2.13]

- Changed
  - Use linked TCD for the slave TX end byte instead of writing the last byte in the EDMA callback.

[2.2.12]

- Bug Fixes
  - Fixed the issue that EDMA transfer configuration use wrong parameter.

[2.2.11]

- Improvements
  - Fixed Coverity CERT-C violations.

[2.2.10]

- Bug Fixes
  - Fixed the issue that slave start event is cleared when it has not been handled.
- Added
  - Supported I3C HDR-DDR transfer with EDMA.
- Changed
  - Used linked EDMA to transfer all I3C subaddress and data without handling of intermediate states, simplifying code logic.
  - Prepare DMA before I3C START to ensure there's no time delay between START and transmitting data.
  - Added the MCTRLDONE flag check after START and STOP request to ensure all states are handled properly.

[2.2.9]

- Bug Fixes
  - Fixed MISRA issue rule 11.3.
  - Added the master control done flag waiting code after STOP in case the bus is not idle when transfer function finishes.

[2.2.8]

- Improvements
  - Removed I3C IRQ handler calling in the EDMA callback. Previously driver doesn't use the END byte which can trigger the STOP interrupt for controller sending and receiving, now let I3C event handler deal with all I3C events.
- Bug Fixes
  - Fixed the bug that the END type Tx register is not used when command length or data length is one byte.

[2.2.7]

- Bug Fixes
  - Fixed MISRA issue rule 11.6.

[2.2.6]

- New features
  - Added the I3C private read/write with 0x7E address as start.

[2.2.5]

- Improvements
  - Added the workaround for RT1180 I3C EDMA issue ERR052086.

[2.2.4]

- Bug Fixes
  - Fixed the issue that I3C master sends the last byte data without using the END type register.

[2.2.3]

- Bug Fixes
  - Fixed issue that slave polulates the last byte when Tx FIFO may be full.

[2.2.2]

- Bug Fixes
  - Fixed I3C MISRA issue rule 10.4, 11.3.

[2.2.1]

- Bug Fixes
  - Fixed the issue that I3C slave send the last byte data without using the END type register.
- Improvements
  - There's no need to reserve two bytes FIFO for DMA transfer which is for IP issue workaround.

[2.2.0]

- Improvements
  - Deleted legacy IBI data request code.

[2.1.0]

- Bug Fixes
  - Fixed MISRA issue rule 8.4, 8.6, 11.8.

[2.0.1]

- Bug Fixes
  - Fixed MISRA issue rule 9.1.

[2.0.0]

- Initial version.

INPUTMUX

[2.0.11]

- Bug Fixes
  - Fixed Coverity UNUSED_VALUE finding in INPUTMUX_EnableSignal().

[2.0.10]

- Bug Fixes
  - Fixed CERT-C violations.

[2.0.9]

- Improvements
  - Use INPUTMUX_CLOCKS to initialize the inputmux module clock to adapt to multiple inputmux instances.
  - Modify the API base type from INPUTMUX_Type to void.

[2.0.8]

- Improvements
  - Updated a feature macro usage for function INPUTMUX_EnableSignal.

[2.0.7]

- Improvements
  - Release peripheral from reset if necessary in init function.

[2.0.6]

- Bug Fixes
  - Fixed the documentation wrong in API INPUTMUX_AttachSignal.

[2.0.5]

- Bug Fixes
  - Fixed build error because some devices has no sct.

[2.0.4]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rule 10.4, 12.2 in INPUTMUX_EnableSignal() function.

[2.0.3]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 10.4, 10.7, 12.2.

[2.0.2]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 10.4, 12.2.

[2.0.1]

- Support channel mux setting in INPUTMUX_EnableSignal().

[2.0.0]

- Initial version.

LPADC

[2.11.0]

- New Features
  - Added the LPADC_USE_FIXED_POINT_GAIN_CALCULATION configuration macro. When set to 1, LPADC_FinishAutoCalibration() calculates the gain conversion result with integer-only arithmetic instead of the float/double software library, saving several kB of flash on code size sensitive devices. The fixed point result keeps the gain fraction in Q17.14, so the two least significant bits of the gain conversion result are always zero.

[2.10.3]

- Bug Fixes
  - Fixed MISRA C-2012 essential-type-model violations (Rules 10.1, 10.3, 10.4 and 10.8) in LPADC_FinishAutoCalibration and LPADC_GetOffsetValue.

[2.10.2]

- Improvements
  - Gate the trigger (TCTRL) enums and the trigger-id assert on FSL_FEATURE_ADC_TCTRL_COUNT for every trigger index, so devices with fewer triggers no longer expose unavailable trigger registers.

[2.10.1]

- Improvements
  - Reworked the gain-calibration ratio in LPADC_FinishAutoCalibration to use single-precision (float) arithmetic instead of double-precision, removing the dependency on the libgcc double soft-float routines (__floatsidf, __aeabi_dsub, __aeabi_ddiv, __aeabi_d2f) that were linked into every application using the LPADC driver, reducing ROM footprint.

[2.10.0]

- Improvements
  - Use #if !defined(ADC_TCTRL_COUNT) || (ADC_TCTRL_COUNT > nU) to wrap some configurations because these configurations are invalid/illegal on some SoCs.

[2.9.5]

- Improvements
  - Fix doxygen issue, grouping command should be balanced.

[2.9.4]

- Improvements
  - Update LPADC_GetDefaultConfig, change default conversionAverageMode value to: kLPADC_ConversionAverage128 for 3 bit width. kLPADC_ConversionAverage1024 for 4 bit width.

[2.9.3]

- Improvements
  - Add timeout for while loop code.

[2.9.2]

- Improvements
  - Fixed CERT-C issues.

[2.9.1]

- Bug Fixes
  - Fixed incorrect channel B FIFO selection logic.

[2.9.0]

- Bug Fixes
  - Add code to handle the case where GCC[GAIN_CAL] is a signed number.
  - Split LPADC_FinishAutoCalibration function into two functions.
  - Improved LPADC driver.

[2.8.4]

- Bug Fixes
  - Remove function 'LPADC_SetOffsetValue' assert statement, this statement may cause runtime errors in existing code.

[2.8.3]

- Bug Fixes
  - Fixed SDK lpadc driver examples compile issue, move condition 'commandId < ADC_CV_COUNT' to a more appropriate location.

[2.8.2]

- Bug Fixes
  - Fixed the violations of MISRA C-2012 rule 18.1, 10.3, 10.1 and 10.4.

[2.8.1]

- Bug Fixes
  - Fixed LPADC sample mode enum name mistake.

[2.8.0]

- Improvements
  - Release peripheral from reset if necessary in init function.
- Bug Fixes
  - Fixed function LPADC_GetConvResult() issue.
  - Fixed function LPADC_SetConvCommandConfig() bugs.

[2.7.2]

- Improvements
  - Use feature macros instead of header file macros.
- Bug Fixes
  - Fixed the violations of MISRA C-2012 rule 10.1, 10.3, 10.4 and 14.3.

[2.7.1]

- Improvements
  - Corrected descriptions of several functions.
  - Improved function LPADC_GetOffsetValue and LPADC_SetOffsetValue.
  - Revert changes of feature macros for lpadc.
  - Use feature macros instead of header file macros.
- Bug Fixes
  - Fixed the violations of MISRA C-2012 rule 10.8.
  - Fixed the violations of MISRA C-2012 rule 10.1, 10.3, 10.4 and 14.3.

[2.7.0]

- Improvements
  - Added supports of CFG2 register.
  - Removed some useless macros.

[2.6.2]

- Bug Fixes
  - Fixed the violations of MISRA C-2012 rules.
  - Fixed LPADC driver code compile error issue.

[2.6.1]

- Improvements
  - Updated the use of macros in the driver code.

[2.6.0]

- Improvements
  - Added the API LPADC_SetOffset12BitValue() to configure 12bit ADC conversion offset trim value manually.
  - Added the API LPADC_SetOffset16BitValue() to configure 16bit ADC conversion offset trim value manually.
  - Added API to set offset calibration mode.
  - Added configuration of alternate channel.
  - Updated auto calibration API and added calibration value conversion API.
- New feature
  - Added API LPADC_EnableHardwareTriggerCommandSelection() to enable trigger commands controlled by ADC_ETC.
  - Updated LPADC_DoAutoCalibration() to allow doing something else before the ADC initialization to be totally complete. Enhance initialization duration time of the ADC.
  - Added two new APIs to get/set calibration value.

[2.5.2]

- Improvements
  - Added while loop, LPADC_GetConvResult() will return only when the FIFO will not be empty.

[2.5.1]

- Bug Fixes
  - Fixed some typos in Lpadc driver comments.

[2.5.0]

- Improvements
  - Added missing items to enable trigger interrupts.

[2.4.0]

- New features
  - Added APIs to get/clear trigger status flags.

[2.3.0]

- Improvements
  - Removed LPADC_MeasureTemperature() function for the LPADC supports different temperature sensor calculation equations.

[2.2.1]

- Improvements
  - Optimized LPADC_MeasureTemperature() function to support the specific series with flash solidified calibration value.
  - Clean doxygen warnings.
- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 10.3, rule 10.8 and rule 17.7.

[2.2.0]

- New Feature
  - Added API LPADC_MeasureTemperature() to get correct temperature from the internal sensor.
- Improvements
  - Separated lpadc_conversion_resolution_mode_t with related feature macro.
- Bug Fixes
  - Fixed the violations of MISRA C-2012 rules:
    - Rule 10.3, 10.4, 10.6, 10.7 and 17.7.

[2.1.1]

- Improvements
  - Updated the gain calibration formula.
  - Used feature to segregate the new item kLPADC_TriggerPriorityPreemptSubsequently.

[2.1.0]

- New Features
  - Added the API LPADC_SetOffsetValue() to support configure offset trim value manually.
  - Added the API LPADC_DoOffsetCalibration() to do offset calibration independently.
- Improvements
  - Improved the usage of macros and removed invalid macros.

[2.0.2]

- Improvements
  - Added support for platforms with 2 FIFOs and different calibration measures.

[2.0.1]

- Bug Fixes
  - Ensured the API LPADC_SetConvCommandConfig configure related registers correctly.

[2.0.0]

- Initial version.

LPCMP

[2.3.2]

- Improvements
  - Fixed LPCMP CERT-C issues.

[2.3.1]

- Improvements
  - Update LPCMP driver to be compatible with platforms that do not support LPCMP nano power mode selection.

[2.3.0]

- New Feature
  - Added some new features for platforms which support
    - Plus input source selection.
    - Minus input source selection.
    - CMP to DAC link.
- Improvements
  - Removed some new features for platforms which doesn't support
    - Functional clock source selection.
    - DAC high power mode selection.
    - Round Robin clock source selection.
    - Round Robin trigger source selection.
    - Round Robin channel sample numbers setting.
    - Round Robin channel sample time threshold setting.
    - Round Robin internal trigger configuration.

[2.2.0]

- Improvements
  - Change FSL_FEATURE_LPCMP_HAS_NO_CCR0_CMP_STOP_EN to FSL_FEATURE_LPCMP_HAS_CCR0_CMP_STOP_EN.

[2.1.3]

- New Feature
  - Added new macro to handle the case where some instances do not have the CCR0 CMP_STOP_EN bit field.

[2.1.2]

- New Feature
  - Add macros to be compatible with some platforms that do not have the CCR0 CMP_STOP_EN bitfield.

[2.1.1]

- Improvements
  - Release peripheral from reset if necessary in init function.

[2.1.0]

- New Features:
  - Supported round robin mode and window mode feature.

[2.0.3]

- Bug Fixes:
  - Fixed the violation of MISRA-2012 rule 17.7.

[2.0.2]

- Bug Fixes:
  - The current API LPCMP_ClearStatusFlags has to check w1c bits.

[2.0.1]

- Added control macro to enable/disable the CLOCK code in current driver.

[2.0.0]

- Initial version.

LPI2C

[2.6.8]

- Bug Fixes
  - LPI2C_MasterTransferBlocking - added waiting while TX FIFO is not empty.
  - Added a check for an error from the previous transfer in the transfer API (when kLPI2C_TransferNoStopFlag was used).
  - Updated LPI2C_MasterReceive() to return kStatus_InvalidArgument when rxSize is 0.
  - Updated transfer API functions to return kStatus_InvalidArgument when transfer->dataSize is 0 and transfer->direction is kLPI2C_Read.
  - Fixed assert issue in LPI2C_MasterSetBaudRate().
  - Fixed CERT-C issues.
  - Fixed MISRA issues.
  - Improved HIS CCM for LPI2C_MasterTransferBlocking() and LPI2C_SlaveTransferHandleIRQ().

[2.6.7]

- Bug Fixes
  - Fixed MISRA 10.3 and 10.8 issues.
  - Fixed LPI2C_MasterStop() to send I2C STOP in case of error.

[2.6.6]

- Bug Fixes
  - Set handle->chunkSize to 0 in LPI2C_MasterTransferNonBlocking().

[2.6.5]

- Bug Fixes
  - Removed write to STAR register in LPI2C_SlaveTransferHandleIRQ handler in case of kLPI2C_SlaveRepeatedStartDetectFlag or kLPI2C_SlaveStopDetectFlag.
  - Removed configuration of FILTSDA from LPI2C_MasterSetBaudRate().
  - Set minimal possible value for FILTSDA and FILTSCL to 0.
  - Updated configuration of glitch filters in LPI2C_SlaveInit().
  - Set minimal possible value for SCFGR2[CLKHOLD] to 1.
  - Added error check to while loop in LPI2C_TransferStateMachineSendCommand().
- Improvements
  - Removed receive data size limitation in LPI2C_MasterTransferBlocking() and LPI2C_MasterTransferNonBlocking().

[2.6.4]

- Bug Fixes
  - Limited value of filtSda in LPI2C_MasterSetBaudRate().
  - Updated LPI2C_MasterStop() and LPI2C_MasterTransferBlocking() to send I2C STOP also in case of error.
  - Removed unused flag kLPI2C_TransferRepeatedStartFlag.

[2.6.3]

- Bug Fixes
  - Fixed static analysis identified issues.

[2.6.2]

- Improvements
  - Added timeout for while loop in LPI2C_TransferStateMachineSendCommand().

[2.6.1]

- Bug Fixes
  - Fixed coverity issues.

[2.6.0]

- New Feature
  - Added common IRQ handler entry LPI2C_DriverIRQHandler.

[2.5.7]

- Improvements
  - Added support for separated IRQ handlers.

[2.5.6]

- Improvements
  - Conditionally compile interrupt handling code to solve the problem of using this driver on CPU cores that do not support interrupts.

[2.5.5]

- Bug Fixes
  - Fixed LPI2C_SlaveInit() - allow to disable SDA/SCL glitch filter.

[2.5.4]

- Bug Fixes
  - Fixed LPI2C_MasterTransferBlocking() - the return value was sometime affected by call of LPI2C_MasterStop().

[2.5.3]

- Improvements
  - Added handler for LPI2C7 and LPI2C8.

[2.5.2]

- Bug Fixes
  - Fixed ERR051119 to ignore the nak flag when IGNACK=1 in LPI2C_MasterCheckAndClearError.

[2.5.1]

- Bug Fixes
  - Added bus stop incase of bus stall in LPI2C_MasterTransferBlocking.
- Improvements
  - Release peripheral from reset if necessary in init function.

[2.5.0]

- New Features
  - Added new function LPI2C_SlaveEnableAckStall to enable or disable ACKSTALL.

[2.4.1]

- Improvements
  - Before master transfer with transactional APIs, enable master function while disable slave function and vise versa for slave transfer to avoid the one affecting the other.

[2.4.0]

- Improvements
  - Split some functions, fixed CCM problem in file fsl_lpi2c.c.
- Bug Fixes
  - Fixed bug in LPI2C_MasterInit that the MCFGR2's value set in LPI2C_MasterSetBaudRate may be overwritten by mistake.

[2.3.2]

- Improvements
  - Initialized the EDMA configuration structure in the LPI2C EDMA driver.

[2.3.1]

- Improvements
  - Updated LPI2C_GetCyclesForWidth to add the parameter of minimum cycle, because for master SDA/SCL filter, master bus idle/pin low timeout and slave SDA/SCL filter configuration, 0 means disabling the feature and cannot be used.
- Bug Fixes
  - Fixed bug in LPI2C_SlaveTransferHandleIRQ that when restart detect event happens the transfer structure should not be cleared.
  - Fixed bug in LPI2C_RunTransferStateMachine, that when only slave address is transferred or there is still data remaining in tx FIFO the last byte's nack cannot be ignored.
  - Fixed bug in slave filter doze enable, that when FILTDZ is set it means disable rather than enable.
  - Fixed bug in the usage of LPI2C_GetCyclesForWidth. First its return value cannot be used directly to configure the slave FILTSDA, FILTSCL, DATAVD or CLKHOLD, because the real cycle width for them should be FILTSDA+3, FILTSCL+3, FILTSCL+DATAVD+3 and CLKHOLD+3. Second when cycle period is not affected by the prescaler value, prescaler value should be passed as 0 rather than 1.
  - Fixed wrong default setting for LPI2C slave. If enabling the slave tx SCL stall, then the default clock hold time should be set to 250ns according to I2C spec for 100kHz standard mode baudrate.
  - Fixed bug that before pushing command to the tx FIFO the FIFO occupation should be checked first in case FIFO overflow.

[2.3.0]

- New Features
  - Supported reading more than 256 bytes of data in one transfer as master.
  - Added API LPI2C_GetInstance.
- Bug Fixes

  - Fixed bug in LPI2C_MasterTransferAbortEDMA, LPI2C_MasterTransferAbort and LPI2C_MasterTransferHandleIRQ that before sending stop signal whether master is active and whether stop signal has been sent should be checked, to make sure no FIFO error or bus error will be caused.
  - Fixed bug in LPI2C master EDMA transactional layer that the bus error cannot be caught and returned by user callback, by monitoring bus error events in interrupt handler.
  - Fixed bug in LPI2C_GetCyclesForWidth that the parameter used to calculate clock cycle should be 2^prescaler rather than prescaler.
  - Fixed bug in LPI2C_MasterInit that timeout value should be configured after baudrate, since the timeout calculation needs prescaler as parameter which is changed during baudrate configuration.
  - Fixed bug in LPI2C_MasterTransferHandleIRQ and LPI2C_RunTransferStateMachine that when master writes with no stop signal, need to first make sure no data remains in the tx FIFO before finishes the transfer.

[2.2.0]

- Bug Fixes
  - Fixed issue that the SCL high time, start hold time and stop setup time do not meet I2C specification, by changing the configuration of data valid delay, setup hold delay, clock high and low parameters.
  - MISRA C-2012 issue fixed.
    - Fixed rule 8.4, 13.5, 17.7, 20.8.

[2.1.12]

- Bug Fixes
  - Fixed MISRA advisory 15.5 issues.

[2.1.11]

- Bug Fixes
  - Fixed the bug that, during master non-blocking transfer, after the last byte is sent/received, the kLPI2C_MasterNackDetectFlag is expected, so master should not check and clear kLPI2C_MasterNackDetectFlag when remainingBytes is zero, in case FIFO is emptied when stop command has not been sent yet.
  - Fixed the bug that, during non-blocking transfer slave may nack master while master is busy filling tx FIFO, and NDF may not be handled properly.

[2.1.10]

- Bug Fixes
  - MISRA C-2012 issue fixed.
    - Fixed rule 10.3, 14.4, 15.5.
  - Fixed unaligned access issue in LPI2C_RunTransferStateMachine.
  - Fixed uninitialized variable issue in LPI2C_MasterTransferHandleIRQ.

  - Used linked TCD to disable tx and enable rx in read operation to fix the issue that for platform sharing the same DMA request with tx and rx, during LPI2C read operation if interrupt with higher priority happened exactly after command was sent and before tx disabled, potentially both tx and rx could trigger dma and cause trouble.
  - Fixed MISRA issues.
    * Fixed rules 10.1, 10.3, 10.4, 11.6, 11.9, 14.4, 17.7.
  - Fixed the waitTimes variable not re-assignment issue for each byte read.
- New Features
  - Added the IRQHandler for LPI2C5 and LPI2C6 instances.
- Improvements
  - Updated the LPI2C_WAIT_TIMEOUT macro to unified name I2C_RETRY_TIMES.

[2.1.9]

- Bug Fixes
  - Fixed Coverity issue of unchecked return value in I2C_RTOS_Transfer.
  - Fixed Coverity issue of operands did not affect the result in LPI2C_SlaveReceive and LPI2C_SlaveSend.
  - Removed STOP signal wait when NAK detected.
  - Cleared slave repeat start flag before transmission started in LPI2C_SlaveSend/LPI2C_SlaveReceive. The issue was that LPI2C_SlaveSend/LPI2C_SlaveReceive did not handle with the reserved repeat start flag. This caused the next slave to send a break, and the master was always in the receive data status, but could not receive data.

[2.1.8]

- Bug Fixes
  - Fixed the transfer issue with LPI2C_MasterTransferNonBlocking, kLPI2C_TransferNoStopFlag, with the wait transfer done through callback in a way of not doing a blocking transfer.
  - Fixed the issue that STOP signal did not appear in the bus when NAK event occurred.

[2.1.7]

- Bug Fixes
  - Cleared the stopflag before transmission started in LPI2C_SlaveSend/LPI2C_SlaveReceive. The issue was that LPI2C_SlaveSend/LPI2C_SlaveReceive did not handle with the reserved stop flag and caused the next slave to send a break, and the master always stayed in the receive data status but could not receive data.

[2.1.6]

- Bug Fixes
  - Fixed driver MISRA build error and C++ build error in LPI2C_MasterSend and LPI2C_SlaveSend.
  - Reset FIFO in LPI2C Master Transfer functions to avoid any byte still remaining in FIFO during last transfer.

  - Fixed the issue that LPI2C_MasterStop did not return the correct NAK status in the bus for second transfer to the non-existing slave address.

[2.1.5]

- Bug Fixes
  - Extended the Driver IRQ handler to support LPI2C4.
  - Changed to use ARRAY_SIZE(kLpi2cBases) instead of FEATURE COUNT to decide the array size for handle pointer array.

[2.1.4]

- Bug Fixes
  - Fixed the LPI2C_MasterTransferEDMA receive issue when LPI2C shared same request source with TX/RX DMA request. Previously, the API used scatter-gather method, which handled the command transfer first, then the linked TCD which was pre-set with the receive data transfer. The issue was that the TX DMA request and the RX DMA request were both enabled, so when the DMA finished the first command TCD transfer and handled the receive data TCD, the TX DMA request still happened due to empty TX FIFO. The result was that the RX DMA transfer would start without waiting on the expected RX DMA request.
  - Fixed the issue by enabling IntMajor interrupt for the command TCD and checking if there was a linked TCD to disable the TX DMA request in LPI2C_MasterEDMACallback API.

[2.1.3]

- Improvements
  - Added LPI2C_WATI_TIMEOUT macro to allow the user to specify the timeout times for waiting flags in functional API and blocking transfer API.
  - Added LPI2C_MasterTransferBlocking API.

[2.1.2]

- Bug Fixes
  - In LPI2C_SlaveTransferHandleIRQ, reset the slave status to idle when stop flag was detected.

[2.1.1]

- Bug Fixes
  - Disabled the auto-stop feature in eDMA driver. Previously, the auto-stop feature was enabled at transfer when transferring with stop flag. Since transfer was without stop flag and the auto-stop feature was enabled, when starting a new transfer with stop flag, the stop flag would be sent before the new transfer started, causing unsuccesful sending of the start flag, so the transfer could not start.
  - Changed default slave configuration with address stall false.

[2.1.0]

- Improvements
  - API name changed:
    * LPI2C_MasterTransferCreateHandle -> LPI2C_MasterCreateHandle.
    * LPI2C_MasterTransferGetCount -> LPI2C_MasterGetTransferCount.
    * LPI2C_MasterTransferAbort -> LPI2C_MasterAbortTransfer.
    * LPI2C_MasterTransferHandleIRQ -> LPI2C_MasterHandleInterrupt.
    * LPI2C_SlaveTransferCreateHandle -> LPI2C_SlaveCreateHandle.
    * LPI2C_SlaveTransferGetCount -> LPI2C_SlaveGetTransferCount.
    * LPI2C_SlaveTransferAbort -> LPI2C_SlaveAbortTransfer.
    * LPI2C_SlaveTransferHandleIRQ -> LPI2C_SlaveHandleInterrupt.

[2.0.0]

- Initial version.

LPI2C_EDMA

[2.4.9]

- Bug Fixes
  - Fixed CERT-C issues.
  - Fixed MISRA issues.

[2.4.8]

- Bug Fixes
  - Fixed MISRA 10.6 and 14.3 issues.

[2.4.7]

- Bug Fixes
  - Fixed incorrect TX FIFO size (maxTxFifo) in LPI2C_MasterTransferEDMA() and LPI2C_MasterTransferEdmaHandleIRQ().

[2.4.6]

- Bug Fixes
  - Fixed static analysis identified issues.

[2.4.5]

- Improvements
  - Added condition to IRQ handler to check whether the interrupt is enabled - kLPI2C_MasterTxReadyFlag.

[2.4.4]

- Improvements
  - Added support for 2KB data transfer

[2.4.3]

- Improvements
  - Added support for separated IRQ handlers.

[2.4.2]

- Improvements
  - Add EDMA ext API to accommodate more types of EDMA.

[2.4.1]

- Refer LPI2C driver change log 2.0.0 to 2.4.1

LPSPI

[2.7.8]

- Bug Fixes
  - Fixed CERT-C issues.
  - Fixed MISRA issues.
- Improvements
  - Improved HIS CCM.

[2.7.7]

- Bug Fixes
  - Fixed timing parameter setting sequence issue in LPSPI_MasterInit, the timing parameter should only be configured when LPSPI master is disabled.
- Improvements
  - Improved performance of LPSPI_MasterTransferBlocking().

[2.7.6]

- Bug Fixes
  - Fixed calculation of SCK-to-SCK delay.

[2.7.5]

- Bug Fixes
  - Fixed MISRA 10.3, 12,2 and 10.7 issues.

[2.7.4]

- Bug Fixes
  - Clear WIDTH bits from the TCR register before writing a new value in LPSPI_MasterTransferBlocking().

[2.7.3]

- Improvements
  - Added timeout for while loop in LPSPI_MasterTransferWriteAllTxData().
  - Make SPI_RETRY_TIMES configurable by CONFIG_SPI_RETRY_TIMES.

[2.7.2]

- Bug Fixes
  - Fixed coverity issues.

[2.7.1]

- Bug Fixes
  - Workaround for errata ERR050607
  - Workaround for errata ERR010655

[2.7.0]

- New Feature
  - Added common IRQ handler entry LPSPI_DriverIRQHandler.

[2.6.10]

- Improvements
  - Conditionally compile interrupt handling code to solve the problem of using this driver on CPU cores that do not support interrupts.

[2.6.9]

- Bug Fixes
  - Fixed reading of TCR register
  - Workaround for errata ERR050606

[2.6.8]

- Bug Fixes
  - Fixed build error when SPI_RETRY_TIMES is defined to non-zero value.

[2.6.7]

- Bug Fixes
  - Fixed the txData from void * to const void * in transmit API _lpspi_master_handle and _lpspi_slave_handle.

[2.6.6]

- Bug Fixes
  - Added LPSPI register init in LPSPI_MasterInit incase of LPSPI register exist.

[2.6.5]

- Improvements
  - Introduced FSL_FEATURE_LPSPI_HAS_NO_PCSCFG and FSL_FEATURE_LPSPI_HAS_NO_MULTI_WIDTH for conditional compile.
  - Release peripheral from reset if necessary in init function.

[2.6.4]

- Bug Fixes
  - Added LPSPI6_DriverIRQHandler for LPSPI6 instance.

[2.6.3]

- Hot Fixes
  - Added macro switch in function LPSPI_Enable about ERRATA051472.

[2.6.2]

- Bug Fixes
  - Disabled lpspi before LPSPI_MasterSetBaudRate incase of LPSPI opened.

[2.6.1]

- Bug Fixes
  - Fixed return value while calling LPSPI_WaitTxFifoEmpty in function LPSPI_MasterTransferNonBlocking.

[2.6.0]

- Feature
  - Added the new feature of multi-IO SPI .

[2.5.3]

- Bug Fixes
  - Fixed 3-wire txmask of handle vaule reentrant issue.

[2.5.2]

- Bug Fixes
  - Workaround for errata ERR051588 by clearing FIFO after transmit underrun occurs.

[2.5.1]

- Bug Fixes
  - Workaround for errata ERR050456 by resetting the entire module using LPSPIn_CR[RST] bit.

[2.5.0]

- Bug Fixes
  - Workaround for errata ERR011097 to wait the TX FIFO to go empty when writing TCR register and TCR[TXMSK] value is 1.
  - Added API LPSPI_WaitTxFifoEmpty for wait the txfifo to go empty.

[2.4.7]

- Bug Fixes
  - Fixed bug that the SR[REF] would assert if software disabled or enabled the LPSPI module in LPSPI_Enable.

[2.4.6]

- Improvements
  - Moved the configuration of registers for the 3-wire lpspi mode to the LPSPI_MasterInit and LPSPI_SlaveInit function.

[2.4.5]

- Improvements
  - Improved LPSPI_MasterTransferBlocking send performance when frame size is 1-byte.

[2.4.4]

- Bug Fixes
  - Fixed LPSPI_MasterGetDefaultConfig incorrect default inter-transfer delay calculation.

[2.4.3]

- Bug Fixes
  - Fixed bug that the ISR response speed is too slow on some platforms, resulting in the first transmission of overflow, Set proper RX watermarks to reduce the ISR response times.

[2.4.2]

- Bug Fixes
  - Fixed bug that LPSPI_MasterTransferBlocking will modify the parameter txbuff and rxbuff pointer.

[2.4.1]

- Bug Fixes
  - Fixed bug that LPSPI_SlaveTransferNonBlocking can't detect RX error.

[2.4.0]

- Improvements
  - Split some functions, fixed CCM problem in file fsl_lpspi.c.

[2.3.1]

- Improvements
  - Initialized the EDMA configuration structure in the LPSPI EDMA driver.
- Bug Fixes
  - Fixed bug that function LPSPI_MasterTransferBlocking should return after the transfer complete flag is set to make sure the PCS is re-asserted.

[2.3.0]

- New Features
  - Supported the master configuration of sampling the input data using a delayed clock to improve slave setup time.

[2.2.1]

- Bug Fixes
  - Fixed bug in LPSPI_SetPCSContinous when disabling PCS continous mode.

[2.2.0]

- Bug Fixes
  - Fixed bug in 3-wire polling and interrupt transfer that the received data is not correct and the PCS continous mode is not working.

[2.1.0]

- Improvements
  - Improved LPSPI_SlaveTransferHandleIRQ to fill up TX FIFO instead of write one data to TX register which improves the slave transmit performance.
  - Added new functional APIs LPSPI_SelectTransferPCS and LPSPI_SetPCSContinous to support changing PCS selection and PCS continous mode.
- Bug Fixes

  - Fixed bug in non-blocking and EDMA transfer APIs that kStatus_InvalidArgument is returned if user configures 3-wire mode and full-duplex transfer at the same time, but transfer state is already set to kLPSPI_Busy by mistake causing following transfer can not start.
  - Fixed bug when LPSPI slave using EDMA way to transfer, tx should be masked when tx data is null, otherwise in 3-wire mode which tx/rx use the same pin, the received data will be interfered.

[2.0.5]

- Improvements
  - Added timeout mechanism when waiting certain states in transfer driver.
- Bug Fixes
  - Fixed the bug that LPSPI can not transfer large data using EDMA.
  - Fixed MISRA 17.7 issues.
  - Fixed variable overflow issue introduced by MISRA fix.
  - Fixed issue that rxFifoMaxBytes should be calculated according to transfer width rather than FIFO width.
  - Fixed issue that completion flag was not cleared after transfer completed.

[2.0.4]

- Bug Fixes
  - Fixed in LPSPI_MasterTransferBlocking that master rxfifo may overflow in stall condition.
  - Eliminated IAR Pa082 warnings.
  - Fixed MISRA issues.
    * Fixed rules 10.1, 10.3, 10.4, 10.6, 11.9, 14.2, 14.4, 15.7, 17.7.

[2.0.3]

- Bug Fixes
  - Removed LPSPI_Reset from LPSPI_MasterInit and LPSPI_SlaveInit, because this API may glitch the slave select line. If needed, call this function manually.

[2.0.2]

- New Features
  - Added dummy data set up API to allow users to configure the dummy data to be transferred.
  - Enabled the 3-wire mode, SIN and SOUT pins can be configured as input/output pin.

[2.0.1]

- Bug Fixes
  - Fixed the bug that the clock source should be divided by the PRESCALE setting in LPSPI_MasterSetDelayTimes function.

  - Fixed the bug that LPSPI_MasterTransferBlocking function would hang in some corner cases.
- Optimization
  - Added #ifndef/#endif to allow user to change the default TX value at compile time.

[2.0.0]

- Initial version.

LPSPI_EDMA

[2.4.11]

- Bug Fixes
  - Fixed CERT-C issues.
  - Fixed MISRA issues.
- Improvements
  - Improved HIS CCM in LPSPI_MasterTransferEDMALite() and LPSPI_SlaveTransferEDMA().

[2.4.10]

- Bug Fixes
  - Fixed MISRA 10.6 issues.

[2.4.9]

- Improvements
  - Removed unused code from LPSPI_SeparateEdmaReadData().

[2.4.8]

- Improvements
  - Added timeout for while loop in EDMA_LpspiMasterCallback() and EDMA_LpspiSlaveCallback().

[2.4.7]

- Bug Fixes
  - Add macro LPSPI_ALIGN_TCD_SIZE_MASK to align an address to edma_tcd_t size.

[2.4.6]

- Improvements
  - Increased transmit FIFO watermark to ensure whole transmit FIFO will be used during data transfer.

[2.4.5]

- Bug Fixes
  - Fixed reading of TCR register
  - Workaround for errata ERR050606

[2.4.4]

- Improvements
  - Add EDMA ext API to accommodate more types of EDMA.

[2.4.3]

- Improvements
  - Supported 32K bytes transmit in DMA, improve the max datasize in LPSPI_MasterTransferEDMALite.

[2.4.2]

- Improvements
  - Added callback status in EDMA_LpspiMasterCallback and EDMA_LpspiSlaveCallback to check transferDone.

[2.4.1]

- Improvements
  - Add the TXMSK wait after TCR setting.

[2.4.0]

- Improvements
  - Separated LPSPI_MasterTransferEDMA functions to LPSPI_MasterTransferPrepareEDMA and LPSPI_MasterTransferEDMALite to optimize the process of transfer.

LPTMR

[2.2.1]

- Bug Fixes
  - Fix CERT INT31-C issues.

[2.2.0]

- Improvements
  - Updated lptmr_prescaler_clock_select_t, only define the valid options.

[2.1.1]

- Improvements
  - Updated the characters from “PTMR” to “LPTMR” in “FSL_FEATURE_PTMR_HAS_NO_PRESCALER_CLOCK_SOURCE_1_SUPPORT” feature definition.

[2.1.0]

- Improvements
  - Implement for some special devices’ not supporting for all clock sources.
- Bug Fixes
  - Fixed issue when accessing CMR register.

[2.0.2]

- Bug Fixes
  - Fixed MISRA-2012 issues.
    - Rule 10.1.

[2.0.1]

- Improvements
  - Updated the LPTMR driver to support 32-bit CNR and CMR registers in some devices.

[2.0.0]

- Initial version.

LPUART

[2.11.0]

- New Feature
  - Added support to enable transmitter RTS and configure transmitter RTS polarity.
  - Added support to enable Transmit Data Inversion.
- Improvements
  - Updated to work on DSC platform.

[2.10.0]

- New Feature
  - Added support to configure RTS watermark.

[2.9.4]

- Improvements
  - Merged duplicate code.

[2.9.3]

- Improvements
  - Added timeout for while loops in LPUART_Deinit().

[2.9.2]

- Bug Fixes
  - Fixed coverity issues.

[2.9.1]

- Bug Fixes
  - Fixed coverity issues.

[2.9.0]

- New Feature
  - Added support for swap TXD and RXD pins.
  - Added common IRQ handler entry LPUART_DriverIRQHandler.

[2.8.3]

- Improvements
  - Conditionally compile interrupt handling code to solve the problem of using this driver on CPU cores that do not support interrupts.

[2.8.2]

- Bug Fix
  - Fixed the bug that LPUART_TransferEnable16Bit controled by wrong feature macro.

[2.8.1]

- Bug Fixes
  - Fixed issue for MISRA-2012 check.
    - Fixed rule-5.3, rule-5.8, rule-10.4, rule-11.3, rule-11.8.

[2.8.0]

- Improvements
  - Added support of DATA register for 9bit or 10bit data transmit in write and read API. Such as: LPUART_WriteBlocking16bit, LPUART_ReadBlocking16bit, LPUART_TransferEnable16Bit LPUART_WriteNonBlocking16bit, LPUART_ReadNonBlocking16bit.

[2.7.7]

- Bug Fixes
  - Fixed the bug that baud rate calculation overflow when srcClock_Hz is 528MHz.

[2.7.6]

- Bug Fixes
  - Fixed LPUART_EnableInterrupts and LPUART_DisableInterrupts bug that blocks if the LPUART address doesn't support exclusive access.

[2.7.5]

- Improvements
  - Release peripheral from reset if necessary in init function.

[2.7.4]

- Improvements
  - Added support for atomic register accessing in LPUART_EnableInterrupts and LPUART_DisableInterrupts.

[2.7.3]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 15.7.

[2.7.2]

- Bug Fix
  - Fixed the bug that the OSR calculation error when lupart init and lpuart set baud rate.

[2.7.1]

- Improvements
  - Added support for LPUART_BASE_PTRS_NS in security mode in file fsl_lpuart.c.

[2.7.0]

- Improvements
  - Split some functions, fixed CCM problem in file fsl_lpuart.c.

[2.6.0]

- Bug Fixes
  - Fixed bug that when there are multiple lpuart instance, unable to support different ISR.

[2.5.3]

- Bug Fixes
  - Fixed comments by replacing unused status flags kLPUART_NoiseErrorInRxDataRegFlag and kLPUART_ParityErrorInRxDataRegFlag with kLPUART_NoiseErrorFlag and kLPUART_ParityErrorFlag.

[2.5.2]

- Bug Fixes
  - Fixed bug that when setting watermark for TX or RX FIFO, the value may exceed the maximum limit.
- Improvements
  - Added check in LPUART_TransferDMAHandleIRQ and LPUART_TransferEdmaHandleIRQ to ensure if user enables any interrupts other than transfer complete interrupt, the dma transfer is not terminated by mistake.

[2.5.1]

- Improvements
  - Use separate data for TX and RX in lpuart_transfer_t.
- Bug Fixes
  - Fixed bug that when ring buffer is used, if some data is received in ring buffer first before calling LPUART_TransferReceiveNonBlocking, the received data count returned by LPUART_TransferGetReceiveCount is wrong.

[2.5.0]

- Bug Fixes
  - Added missing interrupt enable masks kLPUART_Match1InterruptEnable and kLPUART_Match2InterruptEnable.
  - Fixed bug in LPUART_EnableInterrupts, LPUART_DisableInterrupts and LPUART_GetEnabledInterrupts that the BAUD[LBKDIE] bit field should be soc specific.
  - Fixed bug in LPUART_TransferHandleIRQ that idle line interrupt should be disabled when rx data size is zero.
  - Deleted unused status flags kLPUART_NoiseErrorInRxDataRegFlag and kLPUART_ParityErrorInRxDataRegFlag, since firstly their function are the same as kLPUART_NoiseErrorFlag and kLPUART_ParityErrorFlag, secondly to obtain them one data word must be read out thus interfering with the receiving process.
  - Fixed bug in LPUART_GetStatusFlags that the STAT[LBKDIF], STAT[MA1F] and STAT[MA2F] should be soc specific.
  - Fixed bug in LPUART_ClearStatusFlags that tx/rx FIFO is reset by mistake when clearing flags.
  - Fixed bug in LPUART_TransferHandleIRQ that while clearing idle line flag the other bits should be masked in case other status bits be cleared by accident.
  - Fixed bug of race condition during LPUART transfer using transactional APIs, by disabling and re-enabling the global interrupt before and after critical operations on interrupt enable register.
  - Fixed DMA/eDMA transfer blocking issue by enabling tx idle interrupt after DMA/eDMA transmission finishes.
- New Features
  - Added APIs LPUART_GetRxFifoCount/LPUART_GetTxFifoCount to get rx/tx FIFO data count.
  - Added APIs LPUART_SetRxFifoWatermark/LPUART_SetTxFifoWatermark to set rx/tx FIFO water mark.

[2.4.1]

- Bug Fixes
  - Fixed MISRA advisory 17.7 issues.

[2.4.0]

- New Features
  - Added APIs to configure 9-bit data mode, set slave address and send address.

[2.3.1]

- Bug Fixes
  - Fixed MISRA advisory 15.5 issues.

[2.3.0]

- Improvements
  - Modified LPUART_TransferHandleIRQ so that txState will be set to idle only when all data has been sent out to bus.
  - Modified LPUART_TransferGetSendCount so that this API returns the real byte count that LPUART has sent out rather than the software buffer status.
  - Added timeout mechanism when waiting for certain states in transfer driver.

[2.2.8]

- Bug Fixes
  - Fixed issue for MISRA-2012 check.
    - Fixed rule-10.3, rule-14.4, rule-15.5.
  - Eliminated Pa082 warnings by assigning volatile variables to local variables and using local variables instead.
  - Fixed MISRA issues.
    - Fixed rules 10.1, 10.3, 10.4, 10.8, 14.4, 11.6, 17.7.
- Improvements
  - Added check for kLPUART_TransmissionCompleteFlag in LPUART_WriteBlocking, LPUART_TransferHandleIRQ, LPUART_TransferSendDMACallback and LPUART_SendEDMACallback to ensure all the data would be sent out to bus.
  - Rounded up the calculated sbr value in LPUART_SetBaudRate and LPUART_Init to achieve more acurate baudrate setting. Changed osr from uint32_t to uint8_t since osr's bigest value is 31.
  - Modified LPUART_ReadBlocking so that if more than one receiver errors occur, all status flags will be cleared and the most severe error status will be returned.

[2.2.7]

- Bug Fixes
  - Fixed issue for MISRA-2012 check.
    - Fixed rule-12.1, rule-17.7, rule-14.4, rule-13.3, rule-14.4, rule-10.4, rule-10.8, rule-10.3, rule-10.7, rule-10.1, rule-11.6, rule-13.5, rule-11.3, rule-13.2, rule-8.3.

[2.2.6]

- Bug Fixes
  - Fixed the issue of register's being in repeated reading status while dealing with the IRQ routine.

[2.2.5]

- Bug Fixes
  - Do not set or clear the TIE/RIE bits when using LPUART_EnableTxDMA and LPUART_EnableRxDMA.

[2.2.4]

- Improvements
  - Added hardware flow control function support.
  - Added idle-line-detecting feature in LPUART_TransferNonBlocking function. If an idle line is detected, a callback is triggered with status kStatus_LPUART_IdleLineDetected returned. This feature may be useful when the received Bytes is less than the expected received data size. Before triggering the callback, data in the FIFO (if has FIFO) is read out, and no interrupt will be disabled, except for that the receive data size reaches 0.
  - Enabled the RX FIFO watermark function. With the idle-line-detecting feature enabled, users can set the watermark value to whatever you want (should be less than the RX FIFO size). Data is received and a callback will be triggered when data receive ends.

[2.2.3]

- Improvements
  - Changed parameter type in LPUART_RTOS_Init struct from rtos_lpuart_config to lpuart_rtos_config_t.
- Bug Fixes
  - Disabled LPUART receive interrupt instead of all NVICs when reading data from ring buffer. Otherwise when the ring buffer is used, receive nonblocking method will disable all NVICs to protect the ring buffer. This may has a negative effect on other IPs that are using the interrupt.

[2.2.2]

- Improvements
  - Added software reset feature support.
  - Added software reset API in LPUART_Init.

[2.2.1]

- Improvements
  - Added separate RX/TX IRQ number support.

[2.2.0]

- Improvements
  - Added support of 7 data bits and MSB.

[2.1.1]

- Improvements
  - Removed unnecessary check of event flags and assert in LPUART_RTOS_Receive.
  - Added code to always wait for RX event flag in LPUART_RTOS_Receive.

[2.1.0]

- Improvements
  - Update transactional APIs.

LPUART_EDMA

[2.4.0]

- Refer LPUART driver change log 2.1.0 to 2.4.0

MAU

[2.2.2]

- Bug fix
  - Fixed assert judgment.

[2.2.1]

- Improvements
  - Fixed CERT-C issues.

[2.2.0]

- New Features
  - Support indirect operation in low address.

[2.1.0]

- New Features
  - Add some CMSIS DSP functions.

[2.0.0]

- Initial version.

OPAMP

[2.0.0]

- Initial version.

OSTIMER

[2.3.1]

- New Features
  - Added common IRQ handler entry OSTIMER_DriverIRQHandler.

[2.3.0]

- New Features
  - Added OSTIMER_SetMatchValueSafe() with post-write synchronization and missed-event detection. After writing the match registers, it waits for OSEVENT_CTRL[MATCH_WR_RDY] to clear, then checks whether the match moment has already passed:
    - Returns kStatus_Success and enables the interrupt if the match is still in the future, or if the hardware interrupt flag is already set (ISR fires immediately on enable).
    - Returns kStatus_Fail and leaves the interrupt **disabled** if the match was missed without the hardware capturing it; the caller must handle the missed event.
  - **API selection guide** — OSTIMER_SetMatchValue **vs** OSTIMER_SetMatchValueSafe**:**
    - Use OSTIMER_SetMatchValue() when the delta between now and count is reliably larger than ~7 OSTimer ticks (e.g. > 200 µs at 32 kHz). It omits the post-write MATCH_WR_RDY poll and missed-event check, so it returns faster. It's suitable for **most use cases**.
    - Use OSTIMER_SetMatchValueSafe() when the match delta is small or unpredictable. The extra synchronization cost (~7 OSTimer ticks) is the trade-off for a guaranteed success/fail result.
- Bug Fixes
  - Fixed OSTIMER_GetMatchValue() missing binary-encoded counter guard; it now returns the raw binary value on devices with binary-encoded registers.
- Improvements
  - Removed useless tmp variable in OSTIMER_SetMatchRawValue().
  - Clarified return value type for counter get APIs.

[2.2.6]

- Improvements
  - Drop the check of MATCH_WR_RDY and ostimer counter value in OSTIMER_SetMatchRawValue. In most applications, they are useless and may bring at least 7 OSTimer ticks latency, which is unacceptable when OSTimer is working under slow peripheral clock.

  - Optimize software gray code to binary conversion: replaced loop-based implementation with branchless bitwise operations.

[2.2.5]

- Improvements
  - Support binary encoded ostimer.

[2.2.4]

- Bug Fixes
  - Fixed CERT INT31-C violations.

[2.2.3]

- Improvements
  - Disable and clear pending interrupts before disabling the OSTIMER clock to avoid interrupts being executed when the clock is already disabled.

[2.2.2]

- Improvements
  - Support devices with different OSTIMER instance name.

[2.2.1]

- Improvements
  - Release peripheral from reset if necessary in init function.

[2.2.0]

- Improvements
  - Move the PMC operation out of the OSTIMER driver to board specific files.
  - Added low level APIs to control OSTIMER MATCH and interrupt.

[2.1.2]

- Bug Fixes
  - Fixed MISRA-2012 rule 10.8.

[2.1.1]

- Bug Fixes
  - removes the suffix ‘n’ for some register names and bit fields’ names
- Improvements
  - Added HW CODE GRAY feature supported by CODE GRAY in SYSCTRL register group.

[2.1.0]

- Bug Fixes
  - Added a workaround to fix the issue that no interrupt was reported when user set smaller period.
  - Fixed violation of MISRA C-2012 rule 10.3 and 11.9.
- Improvements
  - Added return value for the two APIs to set match value.
    - OSTIMER_SetMatchRawValue
    - OSTIMER_SetMatchValue

[2.0.3]

- Bug Fixes
  - Fixed violation of MISRA C-2012 rule 10.3, 14.4, 17.7.

[2.0.2]

- Improvements
  - Added support for OSTIMER0

[2.0.1]

- Improvements
  - Removed the software reset function out of the initialization API.
  - Enabled interrupt directly instead of enabling deep sleep interrupt. Users need to enable the deep sleep interrupt in application code if needed.

[2.0.0]

- Initial version.

PORT

[2.5.1]

- Bug Fixes
  - Fix CERT INT31-C issues.
  - Fixed the violations of MISRA C-2012 rules: 10.1.

[2.5.0]

- Bug Fixes
  - Correct the kPORT_MuxAsGpio for some platforms.

[2.4.1]

- Bug Fixes
  - Fixed the violations of MISRA C-2012 rules: 10.1, 10.8 and 14.4.

[2.4.0]

- New Features
  - Updated port_pin_config_t to support input buffer and input invert.

[2.3.0]

- New Features
  - Added new APIs for Electrical Fast Transient(EFT) detect.
  - Added new API to configure port voltage range.

[2.2.0]

- New Features
  - Added new api PORT_EnablePinDoubleDriveStrength.

[2.1.1]

- Bug Fixes
  - Fixed the violations of MISRA C-2012 rules: 10.1, 10.4□11.3□11.8, 14.4.

[2.1.0]

- New Features
  - Updated the driver code to adapt the case of the interrupt configurations in GPIO module. Will move the pin configuration APIs to GPIO module.

[2.0.2]

- Other Changes
  - Added feature guard macros in the driver.

[2.0.1]

- Other Changes
  - Added “const” in function parameter.
  - Updated some enumeration variables’ names.

PWM

[2.10.1]

- Bug Fixes
  - Fixed MISRA C-2012 Rule 17.7, 20.6, 16.3, 10.8

[2.10.0]

- Improvements
  - Added API PWM_EnableLocalForce to perform a software-controlled local force initialization, causing a FORCE_OUT event that latches all pending FORCE-buffered shadow registers (DTSRCSEL, MCTRL[IPOL], SWCOUT) into their active registers.
  - Added API PWM_UpdateCurrentPolarity to selecting which VAL comparator pair drives the complementary output pair. The change takes effect only after a subsequent FORCE_OUT event (e.g. via PWM_EnableLocalForce).

[2.9.4]

- Bug Fixes
  - Fixed CERT INT31-C issues.

[2.9.3]

- Improvements
  - Cherry-pick patch from hal_nxp repository. Enhanced input validation in PWM_SetupPwm by returning kStatus_InvalidArgument when the calculated pulse count exceeds UINT16_MAX, to prevent silent failures when assertions are disabled in production builds.

[2.9.2]

- Improvements
  - Add new API PWM_GetInputCaptureValue to read the value captured from the submodule counter.

[2.9.1]

- Improvements
  - Add new API PWM_SetupFaultsExt and PWM_SetupFaultInputFilterExt to support FlexPWM which has more than one fault input channels.
  - Support fault 4-7 interrupt and its flag.
- Bug Fixes
  - Fixed violations of the CERT INT31-C.

[2.9.0]

- Improvements
  - Support PWMX channel output for edge aligned PWM.
  - Forbid submodule 0 counter initialize with master sync and master reload mode.
  - Clarify kPWM_BusClock meaning.
  - Verify pulseCnt within 65535 when update period register.

[2.8.4]

- Improvements
  - Support workaround for ERR051989. This function helps realize no phase delay between submodule 0 and other submodule.

[2.8.3]

- Bug Fixes
  - Fixed MISRA C-2012 Rule 15.7

[2.8.2]

- Bug Fixes
  - Fixed warning conversion from 'int' to 'uint16_t' on API PWM_Init.
  - Fixed warning unused variable 'reg' on API PWM_SetPwmForceOutputToZero.

[2.8.1]

- Improvements
  - Release peripheral from reset if necessary in init function.

[2.8.0]

- Improvements
  - Added API PWM_UpdatePwmPeriodAndDutycycle to update the PWM signal's period and dutycycle for a PWM submodule.
  - Added API PWM_SetPeriodRegister and PWM_SetDutycycleRegister to merge duplicate code in API PWM_SetupPwm, PWM_UpdatePwmDutycycleHighAccuracy and PWM_UpdatePwmPeriodAndDutycycle

[2.7.1]

- Improvements
  - Supported UPDATE_MASK bit in MASK register.

[2.7.0]

- Improvements
  - Supported platforms which don't have Capture feature with channel A and B.
  - Supported platforms which don't have Submodule 3.
  - Added assert function in API PWM_SetPhaseDelay to prevent wrong argument.

[2.6.1]

- Bug Fixes
  - Fixed violations of MISRA C-2012 rules: 10.3.

[2.6.0]

- Improvements
  - Added API PWM_SetPhaseDelay to set the phase delay from the master sync signal of submodule 0.
  - Added API PWM_SetFilterSampleCountthe to set number of consecutive samples that must agree prior to the input filter.
  - Added API PWM_SetFilterSamplePeriod to set set the sampling period of the fault pin input filter.

[2.5.1]

- Bug Fixes
  - Fixed MISRA C-2012 rules: 10.1, 10.3, 10.4 , 10.6 and 10.8.
  - Fixed the issue that PWM_UpdatePwmDutycycle() can't update duty cycle status value correct.

[2.5.0]

- Improvements
  - Added API PWM_SetOouputToIdle to set pwm channel output to idle.
  - Added API PWM_GetPwmChannelState to get the pwm channel output duty cycle value.
  - Added API PWM_SetPwmForceOutputToZero to set the pwm channel output to zero logic.
  - Added API PWM_SetChannelOutput to set the pwm channel output state.
  - Added API PWM_SetClockMode to set the value of the clock prescaler.
  - Added API PWM_SetupPwmPhaseShift to set PWM which a special phase shift and 50% duty cycle.
  - Added API PWM_SetVALxValue/PWM_GetVALxValue to set/get PWM VALs registers values directly.

[2.4.0]

- Improvements
  - Supported the PWM which can't work in wait mode.

[2.3.0]

- Improvements
  - Add PWM output enable&disbale API for SDK.
- Bug Fixes
  - Fixed changing channel B configuration when parameter is kPWM_PWMX and PWMX configuration is not supported yet.

[2.2.1]

- Bug Fixes
  - Fixed violations of MISRA C-2012 rules: 10.3, 10.4.
- Bug Fixes
  - Fixed the issue that PWM drivers computed VAL1 improperly.
- Improvements
  - Updated calculation accuracy of reloadValue in dutyCycleToReloadValue function.

[2.2.0]

- Improvements
  - Added new enumeration and two APIs to support enabling and disabling one or more PWM output triggers.
  - Added a new function to make the most of 16-bit resolution PWM.
  - Added one API to support updating fault status of PWM output.
  - Added one API to support PWM DMA write request.
  - Added three APIs to support PWM DMA capture read request.
  - Added one API to support get default fault config of PWM.
  - Added one API to support setting PWM fault disable mapping.

[2.1.0]

- Improvements
  - Moved the configuration of fault input filter into a new API to avoid be initialized multiple times.
- Bug Fixes
  - MISRA C-2012 issue fixed.
    - Fix rules, containing: rule-10.2, rule-10.3, rule-10.4, rule-10.7, rule-10.8, rule-14.4, rule-16.4.

[2.0.1]

- Bug Fixes
  - Fixed the issue that PWM submodule may be initialized twice in function PWM_SetupPwm().

[2.0.0]

- Initial version.

RESET

[2.4.1]

- Added configurable timeout support for endless while loop.

[2.0.0]

- Initial version.

RTC

[2.4.0]

- New features
  - Add support for RTC clock output.
  - Add support for RTC time seconds interrupt configuration.

[2.3.3]

- Bug Fixes
  - Fix RTC_GetDatetime function validating datetime issue.

[2.3.2]

- Improvements
  - Handle errata 010716: Disable the counter before setting alarm register and then reenable the counter.

[2.3.1]

- Bug Fixes
  - Fixed CERT INT31-C violations.

[2.3.0]

- Improvements
  - Added API RTC_EnableLPOClock to set 1kHz LPO clock.
  - Added API RTC_EnableCrystalClock to replace API RTC_SetClockSource.

[2.2.2]

- Improvements
  - Refine _rtc_interrupt_enable order.

[2.2.1]

- Bug Fixes
  - Fixed the issue of Pa082 warning.
  - Fixed the issue of bit field mask checking.
  - Fixed the issue of hard code in RTC_Init.

[2.2.0]

- Bug Fixes
  - Fixed MISRA C-2012 issue.
    - Fixed rule contain: rule-17.7, rule-14.4, rule-10.4, rule-10.7, rule-10.1, rule-10.3.
  - Fixed central repository code formatting issue.
- Improvements
  - Added an API for enabling wakeup pin.

[2.1.0]

- Improvements
  - Added feature macro check for many features.

[2.0.0]

- Initial version.

SLCD

[2.1.1]

- Improvements
  - Update slcd_duty_cycle_t, slcd_phase_type_t and slcd_phase_index_t, MCXA3xx SoCs only have 48 pins and 4 pack plane phases.
  - Added check for front plane pin index and back plane phase index.

[2.1.0]

- New Features
  - Added new enumerations, updated SLCD_Init and SLCD_GetDefaultConfig to support new low power IP on new SoCs.

[2.0.4]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 10.4.

[2.0.3]

- Bug Fixes
  - Fixed SLCD_Init bug that some bit-fileds are cleared by mistake.

[2.0.2]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 3.1, 10.1, 10.3, 10.3, 10.4 11.4, 17.7

[2.0.1]

- Bug Fixes
  - Changed the Blink mode start setting flow.
- Other Changes
  - Added static to SLCD global variables.

[2.0.0]

- Initial version.

SMARTDMA

[2.14.0]

- Improvements
  - Refine the device specific firmware selection method, use device Kconfig symbol to select.

[2.13.3]

- Bug Fixes
  - Fix RT500 FlexIO QSPI MDK build warning.

[2.13.2]

- Other Changes
  - Add more MCXN devices support.

[2.13.1]

- Other Changes
  - Add more MCXA devices support.

[2.13.0]

- New Features
  - Added MCXA keyscan firmware.
  - Added functions to control CTRL[EXF].

[2.12.0]

- New Features
  - Supported MCXA mculcd and camera functions.

[2.11.0]

- Improvements
  - Make the RT500 QSPI firmware can work with other display firmware in the same project.

[2.10.0]

- New Features
  - Added new camera APIs for MCXN SoCs to support more resolutions.

[2.9.1]

- New Features
  - Supported MCXN235, MCXN236.

[2.9.0]

- New Features
  - Supported MCXN camera functions.
  - Supported user to select individual firmware for MIPI or FLEXIO alone, or both.
  - Added new API of enabling DMA from FlexIO to a Buffer.
  - Added new APIs of setting MIPI-DSI to enter and exit ultra low power state.

[2.8.0]

- New Features
  - Supported converting the pixel data from RGB565 to RGB888.
  - Supported function to turn off certain pixel in a checker board pattern.

[2.7.0]

- New Features
  - Supported data transfer in 2-dimensional way.
  - Supported data transfer in XRGB8888 format and rotate 180 degree.
  - Supported to fill data in whenever there is room in MIPI controller's FIFO rather than using the tx FIFO in double buffered way.

[2.6.3]

- Bug Fixes
  - Fixed EZH_MIPIDSI_RGB565_DMA, EZH_MIPIDSI_RGB888_DMA, EZH_MIPIDSI_ARGB8888toRGB888_DMA issues that don't support some length.

[2.6.2]

- Bug Fixes
  - Fixed MISRA C-2012 issues: 8.4, 11.6, 17.7.

[2.6.1]

- Improvements
  - Optimized MIPI DSI APIs performance.

[2.6.0]

- Improvements
  - Optimized MIPI DSI APIs performance.
- New Features
  - Added new APIs to send MIPI DSI frame with 180 degree rotation.

[2.5.0]

- Improvements
  - Supported swap or don't swap the pixel byte before written to MIPI DSI FIFO.
  - Updated MIPI DSI firmware, make sure data has been sent out before calling callback function.

[2.4.0]

- Improvements
  - Added new APIs for MIPI DSI kSMARTDMA_MIPI_XRGB2RGB_DMA.

[2.3.0]

- Improvements
  - Added new APIs for FlexIO one SHIFTBUF, kSMARTDMA_FlexIO_DMA_ONELANE.
- Bug Fixes
  - Fixed kSMARTDMA_MIPI_RGB565_DMA color bias issue.

[2.2.0]

- Improvements
  - Added new APIs for MIPI DSI, kSMARTDMA_MIPI_RGB565_DMA and kSMARTDMA_MIPI_RGB888_DMA.
  - Supported install firmware and callback function dynamically.

[2.1.0]

- Improvements
  - Removed test APIs, including kSMARTDMA_LightOn, kSMARTDMA_LightOff, kSMARTDMA_Notify, and kSMARTDMA_Test.
  - Added new APIs, including kSMARTDMA_FlexIO_DMA_Reverse, kSMARTDMA_FlexIO_DMA_ARGB2RGB, kSMARTDMA_FlexIO_DMA_ARGB2RGB_Endian_Swap, and kSMARTDMA_FlexIO_DMA_ARGB2RGB_Endian_Swap_Reverse.

[2.0.0]

- Initial version.

MCX_SPC

[2.13.0]

- New Features
  - Added feature macros FSL_FEATURE_MCX_SPC_HAS_IOVDD_HVD and FSL_FEATURE_MCX_SPC_HAS_VD_IO_CFG_LVSEL to be compatible with platforms where the IO VDD voltage detect has no high-voltage detect or no LVSEL bitfield in the VD_IO_CFG register.

[2.12.1]

- Bug Fixes
  - Fixed the bandgap disable sequence in SPC_SetActiveModeRegulatorsConfig() and SPC_SetLowPowerModeRegulatorsConfig(). When disabling bandgap, the regulator drive strength is now configured before writing BGMODE, preventing hardware from forcing BGMODE back to enabled if the previous drive strength was normal.

[2.12.0]

- New Features
  - Add kSPC_controlVbat and kSPC_controlTsi0 to spc_analog_module_control_t for TSI0 and VBAT control support.

[2.11.0]

- New Features
  - Add feature macro FSL_FEATURE_MCX_SPC_HAS_SRAMRETLDO_REFTRIM_REG to be compatible with some platforms where SPC has no SRAMRETLDO_REFTRIM register.

[2.10.1]

- Improvements
  - Add support for some platform does not has Trim for SRAMRETLDO.

[2.10.0]

- New Features
  - Add feature macro to be compatible with some platforms where SPC does not support:
    1. Has no SC register SPC_LP_REQ bitfield.
    2. Has no SC register SPC_LP_MODE bitfield.
    3. Has no PD_STATUS register.
    4. Has no SRAMCTL register.

[2.9.1]

- Improvements

  - There is no need to ensure that the bandgap is enabled before setting the active mode core LDO regulator drive strength and voltage level, because the hardware will automatically turn on the bandgap function if it is required by the hardware when configuring the LDO.

[2.9.0]

- New Features
  - Add feature macro to be compatible with some platforms where SPC does not support overdrive voltage.

[2.8.1]

- Improvements
  - Fixed cert_int31_c_violation of SPC_GetVoltageDetectStatusFlag(), SPC_GetExternalDomainsStatus() and SPC_SetDCDCBurstConfig.

[2.8.0]

- New Features
  - Updated MCX_SPC driver for compatibility with SoCs without PD_STATUS[PWR_REQ_STATUS].

[2.7.0]

- New Features
  - Added new function to unretain RAM array.

[2.6.0]

- Bug Fixes
  - The enumeration kSPC_DeepPowerDownWithSysClockOff should be 0x8U.
- New Features
  - Added functions to get the last low-power mode that the power domain requested.

[2.5.0]

- Improvements
  - Updated SPC_SetLowPowerModeCoreLDORegulatorConfig() with adding check that LP_CFG[CORELDO_VDD_LVL] only be updated when CORELDO is in normal driver strength in active mode.
  - Updated SPC_SetLowPowerModeRegulatorsConfig() with adding check the if DCDC voltage level set as retention mode, CORELDO low voltage detection must be disabled.
  - Updated spc_analog_module_control with adding Opamp3 support.
- New Features
  - Added functions to mask/unmask voltage detections in active mode.

[2.4.2]

- Improvements
  - Fixed the violation of MISRA C-2012 rules.

[2.4.1]

- Improvements
  - Fixed the violation of MISRA C-2012 rules.

[2.4.0]

- Improvements
  - Refined APIs to set regulators, the input parameters will be check firstly before setting register.
  - Improved APIs' document.
  - Removed software check for DCDC's settings since there is not hardware restrictions for DCDC.
  - Added new APIs to check if glitch detector is enabled in active/low power mode.
  - Added new APIs for DCDC burst feature, make it more flexible to use.
  - Added new API to enable/disable DCDC bleed resistor.
  - Set functions of VD_SYS_CFG[LVSEL] configuration as deprecated, since this bit filed is reserved for all devices.
  - Updated details of spc_core_ldo_voltage_level_t to align with description of latest RM, added comments to reminder users that the retention voltage is reserved in some devices.

[2.3.0]

- New Features
  - Updated glitch detect API to support devices which do not have aGDET

[2.2.1]

- Bug Fixes
  - Fixed an issue of SPC_SetActiveModeRegulatorsConfig() which will cause LVD in case of setting DCDC and CORE LDO into higher voltage level.

[2.2.0]

- New Features
  - Added some macros to support some devices(such as MCXA family) do not equipped DCDC, SYS_LDO and so on.
  - Added new function SPC_EnableSRAMLdOLowPowerModeIREF(), SPC_TrimSRAMLdoRefVoltage(), SPC_EnableSRAMLdo() to support some devices(such as MCXA family) that support control of SRAM_LDO.
  - Fixed violation of MISRA C-2012 rule 17.7.
  - Fixed an issue in SPC_SetLowPowerModeRegulatorsConfig() function that set ACTIVE_CFG register by mistake.

[2.1.0]

- Improvements
  - Added new functions to set regulators' voltage level and drive strength individually.
  - Updated SPC_SetActiveModeRegulatorsConfig() and SPC_SetLowPowerModeRegulatorsConfig() based on new added functions.

[2.0.1]

- Bug Fixes
  - Fixed a bug that external burst not working properly.
  - Fixed a bug that is SPC has VDD_DS the voltage is not configured correctly.

[2.0.0]

- Initial version.

TDET

[2.4.0]

- Added support for MIMXRT2663.

[2.3.3]

- Fix MISRA and CERT-C findings.

[2.3.2]

- New Features
  - Added common IRQ handler entry TDET_DriverIRQHandler.

[2.3.1]

- Added support for KW43 device.

[2.3.0]

- Added enum for TIF10.

[2.2.0]

- Added support for chips without active tamper pins.

[2.1.1]

- Added clearing SR_TAF and SR_DTF into TDET_Init().
  - Fix typo in kTDET_ClockType64Hz comment.

[2.1.0]

- Added setting of disabling prescaler on tamper event into TDET_SetConfig() and TDET_GetDefaultConfig functions.

[2.0.0]

- Initial version.

TRDC

[2.2.3]

- Improvements
  - Fix DERRLOC MBCINST decode for flat-encoding devices

[2.2.2]

- Improvements
  - Update APIs to check whether the memory access configuration can be updated.
  - Update APIs to mask the MRC address since only high 18 bits are valid.

[2.2.1]

- Bug Fixes:
  - Fix MISRA violations.

[2.2.0]

- New Features:
  - Supported SoCs that do not have all TRDC modules.

[2.1.0]

- Bug Fixes:
  - Fix MISRA violations.
  - Fixed wrong operation of domain mask in TRDC_MbcNseClearAll and TRDC_MrcDomainNseClear.

[2.0.0]

- Initial version.

TRNG

[2.0.23]

- New features:
  - Updated TRNG default values for MCXA577 devices based on silicon characterization.

[2.0.22]

- New features:
  - Added support for KW43 and MCXW70 devices.

[2.0.21]

- New features:
  - Added support for MCXC devices.

[2.0.20]

- New features:
  - Added support for MCXA devices.

[2.0.19]

- New features:
  - Added support for MCXA and MCXL.

[2.0.18]

- Bug fix:
  - TRNG health checks now done in software on RT5xx and RT6xx.

[2.0.17]

- New features:
  - Add support for RT700.

[2.0.16]

- Improvements:
  - Added support for Dual oscillator mode.

[2.0.15]

- Other changes:
  - Changed TRNG_USER_CONFIG_DEFAULT_XXX values according to latest reccomended by design team.

[2.0.14]

- New features:
  - Add support for RW610 and RW612.

[2.0.13]

- Bug fix:
  - After deepsleep it might return error, added clearing bits in TRNG_GetRandomData() and generating new entropy.
  - Modified reloading entropy in TRNG_GetRandomData(), for some data length it doesn't reloading entropy correctly.

[2.0.12]

- Bug fix:
  - For KW34A4_SERIES, KW35A4_SERIES, KW36A4_SERIES set TRNG_USER_CONFIG_DEFAULT_OSC_DIV to kTRNG_RingOscDiv8.

[2.0.11]

- Bug fix:
  - Add clearing pending errors in TRNG_Init().

[2.0.10]

- Bug Fix:
  - Fixed doxygen issues.

[2.0.9]

- Bug Fix:
  - Fix HIS_CCM metrics issues.

[2.0.8]

- Bug fix:
  - For K32L2A41A_SERIES set TRNG_USER_CONFIG_DEFAULT_OSC_DIV to kTRNG_RingOscDiv4.

[2.0.7]

- Bug fix:
  - Fix MISRA 2004 issue rule 12.5.

[2.0.6]

- Bug fix:
  - For KW35Z4_SERIES set TRNG_USER_CONFIG_DEFAULT_OSC_DIV to kTRNG_RingOscDiv8.

[2.0.5]

- Improvements:
  - For FRQMIN, FRQMAX and OSCDIV, add possibility to use device specific preprocessor macro to define default value in TRNG user configuration structure.

[2.0.4]

- Bug Fix:
  - Fix MISRA-2012 issues.
    - Rule 10.1, rule 10.3, rule 13.5, rule 16.1.

[2.0.3]

- Improvements:
  - update TRNG_Init to restart new entropy generation.

[2.0.2]

- Improvements:
  - fix MISRA issues
    - Rule 14.4.

[2.0.1]

- New features:
  - Set default OSCDIV for Kinetis devices KL8x and KL28Z.
- Other changes:
  - Changed default OSCDIV for K81 to divide by 2.

[2.0.0]

- Initial version.

UTICK

[2.0.6]

- New Features
  - Added common IRQ handler entry UTICK_CommonDriverIRQHandler.

[2.0.5]

- Improvements
  - Improved for SOC RW610.

[2.0.4]

- Bug Fixes
  - Fixed compile fail issue of no-supporting PD configuration in utick driver.

[2.0.3]

- Bug Fixes
  - Fixed violations of MISRA C-2012 rules: 8.4, 14.4, 17.7

[2.0.2]

- Added new feature definition macro to enable/disable power control in drivers for some devices have no power control function.

[2.0.1]

- Added control macro to enable/disable the CLOCK code in current driver.

[2.0.0]

- Initial version.

MCX_VBAT

[2.6.0]

- New features
  - Support new SoC. On the new SoC the following VBAT features are removed:
    - OSCCTLA[MODE_EN] oscillator operate-mode select
    - OSCCFGA switch-mode comparator/delay/capacitor trim (CMP_TRIM/DLY_TRIM/CAP_TRIM)
    - Extended STATUSA/IRQENA flags (wakeup-pin, bandgap timer0/1, LDO ready, interrupt 0-3)
    - WAKENA, WAKECFG and LOCKA registers

    and the following VBAT features are added:
    - STATUSA/IRQENA POR-detect and OSC32K-ready status flags and interrupts

[2.5.0]

- New features
  - Update MCX_VBAT driver to be compatible with new platforms.

[2.4.0]

- New features
  - Update MCX_VBAT driver to be compatible with new platforms.

[2.3.1]

- Bug Fixes
  - Fixed violations of MISRA C-2012 low impact rules.

[2.3.0]

- Improvements
  - OSCCTLA[FINE_AMP_GAIN] is reserved, added new macro to support this change.
  - Defined VBAT_LDORAMC_RET in case of this macro is not defined in header file.
- Bug Fixes
  - Fixed violaltions of MISRA C-2012 rule 10.8.

[2.2.0]

- Improvements
  - Added macros to support some devices(such as MCXA family) that do not support OSC control, LDO control, bandgap timer, and tamper.

[2.1.0]

- New features
  - Added functions to support tamper and clock monitor.

[2.0.0]

- Initial version.

WAKETIMER

[2.0.2]

- New Features
  - Added common IRQ handler entry WAKETIMER_DriverIRQHandler.

[2.0.1]

- Bug Fix
  - MISRA C-2012 issue fixed: rule 8.2, 8.8, 10.1, 10.4.

[2.0.0]

- Initial version.

WUU

[2.4.2]

- Bug Fixes
  - Fixed violations of CERT-C:
    - Check filterIndex >= 1U to prevent underflow.
    - Check multiplication results fit in uint8_t before assignment to shift variable.

[2.4.1]

- Improvements
  - The semantics of kWUU_FilterActiveDSPD and kWUU_ExternalPinActiveDSPD are not clear enough, because on some platforms it's not 'DSPD' (deep sleep, power down) but PDDPD (power down, deep power down). We deprecate them and will use the more generic kWUU_FilterActiveLowLeakage and kWUU_ExternalPinActiveLowLeakage in the future.

[2.4.0]

- New Features
  - Added WUU_ClearExternalWakeupPinsConfig() to clear settings of PDC and PE register.

[2.3.0]

- New Features
  - Added WUU_ClearInternalWakeUpModulesConfig() to clear settings of DM and ME register.

[2.2.1]

- Bug Fixes
  - Fixed WUU_SetPinFilterConfig() unable to set edge detection of pin filter config.
  - Fixed wrong macro used in WUU_GetPinFilterFlag() function.

[2.2.0]

- New Features
  - Added the WUU_GetExternalWakeupPinFlag() and WUU_ClearExternalWakeupPinFlag() function .

[2.1.0]

- New Features
  - Added the WUU_GetModuleInterruptFlag() function to support the devices that equipped MF register.

[2.0.0]

- Initial version.

WWDT

[2.1.11]

- Bug Fixes
  - Fixed CERT INT31-C static analysis finding by clamping boolean configuration values (WDEN/WDRESET/LOCK) to 0/1 before writing the MOD register in WWDT_Init.

[2.1.10]

- Bug Fixes
  - Chek WWDT_RSTS instead of FSL_FEATURE_WWDT_HAS_NO_RESET to determine whether the peripheral can be reset.

[2.1.9]

- Bug Fixes
  - Fixed violation of the MISRA C-2012 rule 10.4.

[2.1.8]

- Improvements
  - Updated the “WWDT_Init” API to add wait operation. Which can avoid the TV value read by CPU still be 0xFF (reset value) after WWDT_Init function returns.

[2.1.7]

- Bug Fixes
  - Fixed the issue that the watchdog reset event affected the system from PMC.
  - Fixed the issue of setting watchdog WDPROTECT field without considering the backwards compatibility.
  - Fixed the issue of clearing bit fields by mistake in the function of WWDT_ClearStatusFlags.

[2.1.5]

- Bug Fixes
  - deprecated a unusable API in WWWDT driver.
    - WWDT_Disable

[2.1.4]

- Bug Fixes
  - Fixed violation of the MISRA C-2012 rules Rule 10.1, 10.3, 10.4 and 11.9.
  - Fixed the issue of the inseparable process interrupted by other interrupt source.
    - WWDT_Init

[2.1.3]

- Bug Fixes
  - Fixed legacy issue when initializing the MOD register.

[2.1.2]

- Improvements
  - Updated the “WWDT_ClearStatusFlags” API and “WWDT_GetStatusFlags” API to match QN9090. WDTOF is not set in case of WD reset. Get info from PMC instead.

[2.1.1]

- New Features
  - Added new feature definition macro for devices which have no LCOK control bit in MOD register.
  - Implemented delay/retry in WWDT driver.

[2.1.0]

- Improvements
  - Added new parameter in configuration when initializing WWDT module. This parameter, which must be set, allows the user to deliver the WWDT clock frequency.

[2.0.0]

- Initial version.

1.7 Driver API Reference Manual

This section provides a link to the Driver API RM, detailing available drivers and their usage to help you integrate hardware efficiently.

MCXA366

1.8 Middleware Documentation

Find links to detailed middleware documentation for key components. While not all onboard middleware is covered, this serves as a useful reference for configuration and development.

1.8.1 MCU Boot

mcuboot_opensource

1.8.2 FreeMASTER

freemaster

1.8.3 FreeRTOS

FreeRTOS

1.8.4 File systemFatfs

FatFs

Chapter 2

MCXA366

2.1 AOI: Crossbar AND/OR/INVERT Driver

void AOI_Init(AOI_Type *base)

Initializes an AOI instance for operation.

This function un-gates the AOI clock.

Parameters

- base – AOI peripheral address.

void AOI_Deinit(AOI_Type *base)

Deinitializes an AOI instance for operation.

This function shutdowns AOI module.

Parameters

- base – AOI peripheral address.

void AOI_GetEventLogicConfig(AOI_Type *base, *aoi_event_t* event, *aoi_event_config_t* *config)

Gets the Boolean evaluation associated.

This function returns the Boolean evaluation associated.

Example:

```
aoi_event_config_t demoEventLogicStruct;

AOI_GetEventLogicConfig(AOI, kAOI_Event0, &demoEventLogicStruct);
```

Parameters

- base – AOI peripheral address.
- event – Index of the event which will be set of type aoi_event_t.
- config – Selected input configuration .

void AOI_SetEventLogicConfig(AOI_Type *base, *aoi_event_t* event, const *aoi_event_config_t* *eventConfig)

Configures an AOI event.

This function configures an AOI event according to the aoiEventConfig structure. This function configures all inputs (A, B, C, and D) of all product terms (0, 1, 2, and 3) of a desired event.

Example:

```
aoi_event_config_t demoEventLogicStruct;

demoEventLogicStruct.PT0AC = kAOI_InvInputSignal;
demoEventLogicStruct.PT0BC = kAOI_InputSignal;
demoEventLogicStruct.PT0CC = kAOI_LogicOne;
demoEventLogicStruct.PT0DC = kAOI_LogicOne;

demoEventLogicStruct.PT1AC = kAOI_LogicZero;
demoEventLogicStruct.PT1BC = kAOI_LogicOne;
demoEventLogicStruct.PT1CC = kAOI_LogicOne;
demoEventLogicStruct.PT1DC = kAOI_LogicOne;

demoEventLogicStruct.PT2AC = kAOI_LogicZero;
demoEventLogicStruct.PT2BC = kAOI_LogicOne;
demoEventLogicStruct.PT2CC = kAOI_LogicOne;
demoEventLogicStruct.PT2DC = kAOI_LogicOne;

demoEventLogicStruct.PT3AC = kAOI_LogicZero;
demoEventLogicStruct.PT3BC = kAOI_LogicOne;
demoEventLogicStruct.PT3CC = kAOI_LogicOne;
demoEventLogicStruct.PT3DC = kAOI_LogicOne;

AOI_SetEventLogicConfig(AOI, kAOI_Event0, demoEventLogicStruct);
```

Parameters

- base – AOI peripheral address.
- event – Event which will be configured of type aoi_event_t.
- eventConfig – Pointer to type aoi_event_config_t structure. The user is responsible for filling out the members of this structure and passing the pointer to this function.

FSL_AOI_DRIVER_VERSION

Version 2.0.2.

enum _aoi_input_config

AOI input configurations.

The selection item represents the Boolean evaluations.

Values:

enumerator kAOI_LogicZero

Forces the input to logical zero.

enumerator kAOI_InputSignal

Passes the input signal.

enumerator kAOI_InvInputSignal

Inverts the input signal.

enumerator kAOI_LogicOne

Forces the input to logical one.

enum _aoi_event

AOI event indexes, where an event is the collection of the four product terms (0, 1, 2, and 3) and the four signal inputs (A, B, C, and D).

Values:

enumerator kAOI_Event0

Event 0 index

enumerator kAOI_Event1

Event 1 index

enumerator kAOI_Event2

Event 2 index

enumerator kAOI_Event3

Event 3 index

typedef enum *_aoi_input_config* aoi_input_config_t

AOI input configurations.

The selection item represents the Boolean evaluations.

typedef enum *_aoi_event* aoi_event_t

AOI event indexes, where an event is the collection of the four product terms (0, 1, 2, and 3) and the four signal inputs (A, B, C, and D).

typedef struct *_aoi_event_config* aoi_event_config_t

AOI event configuration structure.

Defines structure *_aoi_event_config* and use the *AOI_SetEventLogicConfig()* function to make whole event configuration.

AOI

AOI peripheral address

struct _aoi_event_config

#include <fsl_aoi.h> AOI event configuration structure.

Defines structure *_aoi_event_config* and use the *AOI_SetEventLogicConfig()* function to make whole event configuration.

Public Members

aoi_input_config_t PT0AC

Product term 0 input A

aoi_input_config_t PT0BC

Product term 0 input B

aoi_input_config_t PT0CC
Product term 0 input C

aoi_input_config_t PT0DC
Product term 0 input D

aoi_input_config_t PT1AC
Product term 1 input A

aoi_input_config_t PT1BC
Product term 1 input B

aoi_input_config_t PT1CC
Product term 1 input C

aoi_input_config_t PT1DC
Product term 1 input D

aoi_input_config_t PT2AC
Product term 2 input A

aoi_input_config_t PT2BC
Product term 2 input B

aoi_input_config_t PT2CC
Product term 2 input C

aoi_input_config_t PT2DC
Product term 2 input D

aoi_input_config_t PT3AC
Product term 3 input A

aoi_input_config_t PT3BC
Product term 3 input B

aoi_input_config_t PT3CC
Product term 3 input C

aoi_input_config_t PT3DC
Product term 3 input D

2.2 CACHE: LPCAC CACHE Memory Controller

static inline void L1CACHE_EnableCodeCache(void)
Enables the processor code bus cache.

static inline void L1CACHE_DisableCodeCache(void)

Disables the processor code bus cache.

static inline void L1CACHE_InvalidateCodeCache(void)

Clears cache.

Note: LPCAC_CTRL[CLR_LPCAC] is a sticky bit: writing 1 clears (invalidates) the cache, and the cache is held cleared until the bit is written back to 0. This function therefore sets the bit and then clears it, with a memory barrier in between, so the cache is invalidated and left in a valid (operational) state.

---

static inline void L1CACHE_EnableAllocation(void)

Enables allocation.

static inline void L1CACHE_DisableAllocation(void)

Disables allocation.

static inline void L1CACHE_EnableParity(void)

Enables parity.

static inline void L1CACHE_DisableParity(void)

Disable parity.

FSL_CACHE_LPCAC_DRIVER_VERSION

cache driver version

2.3 CDOG

status_t CDOG_Init(CDOG_Type *base, *cdog_config_t* *conf)

Initialize CDOG.

This function initializes CDOG block and setting.

Parameters

- base – CDOG peripheral base address
- conf – CDOG configuration structure

Returns

Status of the init operation

void CDOG_Deinit(CDOG_Type *base)

Deinitialize CDOG.

This function deinitializes CDOG secure counter.

Parameters

- base – CDOG peripheral base address

void CDOG_GetDefaultConfig(*cdog_config_t* *conf)

Sets the default configuration of CDOG.

This function initialize CDOG config structure to default values.

Parameters

- conf – CDOG configuration structure

void CDOG_Stop(CDOG_Type *base, uint32_t stop)

Stops secure counter and instruction timer.

This function stops instruction timer and secure counter. This also change state od CDOG to IDLE.

Parameters

- base – CDOG peripheral base address
- stop – expected value which will be compared with value of secure counter

void CDOG_Start(CDOG_Type *base, uint32_t reload, uint32_t start)

Sets secure counter and instruction timer values.

This function sets value in RELOAD and START registers for instruction timer and secure counter

Parameters

- base – CDOG peripheral base address
- reload – reload value
- start – start value

void CDOG_Check(CDOG_Type *base, uint32_t check)

Checks secure counter.

This function compares stop value in handler with secure counter value by writting to RELOAD refister.

Parameters

- base – CDOG peripheral base address
- check – expected (stop) value

void CDOG_Set(CDOG_Type *base, uint32_t stop, uint32_t reload, uint32_t start)

Sets secure counter and instruction timer values.

This function sets value in STOP, RELOAD and START registers for instruction timer and secure counter.

Parameters

- base – CDOG peripheral base address
- stop – expected value which will be compared with value of secure counter
- reload – reload value for instruction timer
- start – start value for secure timer

void CDOG_Add(CDOG_Type *base, uint32_t add)

Add value to secure counter.

This function add specified value to secure counter.

Parameters

- base – CDOG peripheral base address.
- add – Value to be added.

void CDOG_Add1(CDOG_Type *base)

Add 1 to secure counter.

This function add 1 to secure counter.

Parameters

- base – CDOG peripheral base address.

void CDOG_Add16(CDOG_Type *base)

Add 16 to secure counter.

This function add 16 to secure counter.

Parameters

- base – CDOG peripheral base address.

void CDOG_Add256(CDOG_Type *base)

Add 256 to secure counter.

This function add 256 to secure counter.

Parameters

- base – CDOG peripheral base address.

void CDOG_Sub(CDOG_Type *base, uint32_t sub)

brief Substract value to secure counter

This function substract specified value to secure counter.

param base CDOG peripheral base address. param sub Value to be substracted.

void CDOG_Sub1(CDOG_Type *base)

Substract 1 from secure counter.

This function substract specified 1 from secure counter.

Parameters

- base – CDOG peripheral base address.

void CDOG_Sub16(CDOG_Type *base)

Substract 16 from secure counter.

This function substract specified 16 from secure counter.

Parameters

- base – CDOG peripheral base address.

void CDOG_Sub256(CDOG_Type *base)

Substract 256 from secure counter.

This function substract specified 256 from secure counter.

Parameters

- base – CDOG peripheral base address.

void CDOG_WritePersistent(CDOG_Type *base, uint32_t value)

Set the CDOG persistent word.

Parameters

- base – CDOG peripheral base address.
- value – The value to be written.

uint32_t CDOG_ReadPersistent(CDOG_Type *base)

Get the CDOG persistent word.

Parameters

- base – CDOG peripheral base address.

Returns

The persistent word.

FSL_CDOG_DRIVER_VERSION

Defines CDOG driver version 2.1.3.

Change log:

- Version 2.1.3
  - Re-design multiple instance IRQs and Clocks
  - Add fix for RESTART command errata
- Version 2.1.2
  - Support multiple IRQs
  - Fix default CONTROL values
- Version 2.1.1
  - Remove bit CONTROL[CONTROL_CTRL]
- Version 2.1.0
  - Rename CWT to CDOG
- Version 2.0.2
  - Fix MISRA-2012 issues
- Version 2.0.1
  - Fix doxygen issues
- Version 2.0.0
  - initial version

enum ___cdog_debug_Action_ctrl_enum

Values:

enumerator kCDOG_DebugHaltCtrl_Run

enumerator kCDOG_DebugHaltCtrl_Pause

enum ___cdog_irq_pause_ctrl_enum

Values:

enumerator kCDOG_IrqPauseCtrl_Run

enumerator kCDOG_IrqPauseCtrl_Pause

enum ___cdog_fault_ctrl_enum

Values:

enumerator kCDOG_FaultCtrl_EnableReset

enumerator kCDOG_FaultCtrl_EnableInterrupt

enumerator kCDOG_FaultCtrl_NoAction

enum ___code_lock_ctrl_enum

Values:

enumerator kCDOG_LockCtrl_Lock

enumerator kCDOG_LockCtrl_Unlock

typedef uint32_t secure_counter_t

SC_ADD(add)

SC_ADD1

SC_ADD16

SC_ADD256

SC_SUB(sub)

SC_SUB1

SC_SUB16

SC_SUB256

SC_CHECK(val)

struct cdog_config_t

#include <fsl_cdog.h>

2.4 CRC: Cyclic Redundancy Check Driver

FSL_CRC_DRIVER_VERSION

CRC driver version. Version 2.1.0.

Current version: 2.1.0

Change log:

- Version 2.1.0
  - Choosing CRC clocks from CRC clock array according to instance instead of hard-coded value.
- Version 2.0.5
  - Fix CERT-C issue with boolean-to-unsigned integer conversion.
- Version 2.0.4
  - Release peripheral from reset if necessary in init function.
- Version 2.0.3

- Fix MISRA issues

- Version 2.0.2
  - Fix MISRA issues
- Version 2.0.1
  - move DATA and DATALL macro definition from header file to source file

enum _crc_bits

CRC bit width.

Values:

enumerator kCrcBits16

Generate 16-bit CRC code

enumerator kCrcBits32

Generate 32-bit CRC code

enum _crc_result

CRC result type.

Values:

enumerator kCrcFinalChecksum

CRC data register read value is the final checksum. Reflect out and final xor protocol features are applied.

enumerator kCrcIntermediateChecksum

CRC data register read value is intermediate checksum (raw value). Reflect out and final xor protocol feature are not applied. Intermediate checksum can be used as a seed for *CRC_Init()* to continue adding data to this checksum.

typedef enum *_crc_bits* crc_bits_t

CRC bit width.

typedef enum *_crc_result* crc_result_t

CRC result type.

typedef struct *_crc_config* crc_config_t

CRC protocol configuration.

This structure holds the configuration for the CRC protocol.

void CRC_Init(CRC_Type *base, const *crc_config_t* *config)

Enables and configures the CRC peripheral module.

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

Parameters

- base – CRC peripheral address.
- config – CRC module configuration structure.

void CRC_Deinit(CRC_Type *base)

Disables the CRC peripheral module.

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

Parameters

- base – CRC peripheral address.

void CRC_GetDefaultConfig(*crc_config_t* *config)

Loads default values to the CRC protocol configuration structure.

Loads default values to the CRC protocol configuration structure. The default values are as follows.

```
config->polynomial = 0x1021;
config->seed = 0xFFFF;
config->reflectIn = false;
config->reflectOut = false;
config->complementChecksum = false;
config->crcBits = kCrcBits16;
config->crcResult = kCrcFinalChecksum;
```

Parameters

- config – CRC protocol configuration structure.

void CRC_WriteData(CRC_Type *base, const uint8_t *data, size_t dataSize)

Writes data to the CRC module.

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

Parameters

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

uint32_t CRC_Get32bitResult(CRC_Type *base)

Reads the 32-bit checksum from the CRC module.

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

Parameters

- base – CRC peripheral address.

Returns

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

uint16_t CRC_Get16bitResult(CRC_Type *base)

Reads a 16-bit checksum from the CRC module.

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

Parameters

- base – CRC peripheral address.

Returns

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

CRC_DRIVER_USE_CRC16_CCIT_FALSE_AS_DEFAULT

Default configuration structure filled by *CRC_GetDefaultConfig()*. Use CRC16-CCIT-FALSE as defeault.

struct _crc_config

#include <fsl_crc.h> CRC protocol configuration.

This structure holds the configuration for the CRC protocol.

Public Members

uint32_t polynomial

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

uint32_t seed

Starting checksum value

bool reflectIn

Reflect bits on input.

bool reflectOut

Reflect bits on output.

bool complementChecksum

True if the result shall be complement of the actual checksum.

crc_bits_t crcBits

Selects 16- or 32- bit CRC protocol.

crc_result_t crcResult

Selects final or intermediate checksum return from *CRC_Get16bitResult()* or *CRC_Get32bitResult()*

2.5 CTIMER: Standard counter/timers

void CTIMER_Init(CTIMER_Type *base, const *ctimer_config_t* *config)

Ungates the clock and configures the peripheral for basic operation.

Note: This API should be called at the beginning of the application before using the driver.

Parameters

- base – Ctimer peripheral base address
- config – Pointer to the user configuration structure.

void CTIMER_Deinit(CTIMER_Type *base)

Gates the timer clock.

Parameters

- base – Ctimer peripheral base address

void CTIMER_GetDefaultConfig(*ctimer_config_t* *config)

Fills in the timers configuration structure with the default settings.

The default values are:

```
config->mode = kCTIMER_TimerMode;
config->input = kCTIMER_Capture_0;
config->prescale = 0;
```

Parameters

- config – Pointer to the user configuration structure.

status_t CTIMER_SetupPwmPeriod(CTIMER_Type *base, const *ctimer_match_t* pwmPeriodChannel, *ctimer_match_t* matchChannel, uint32_t pwmPeriod, uint32_t pulsePeriod, bool enableInt)

Configures the PWM signal parameters.

Enables PWM mode on the match channel passed in and will then setup the match value and other match parameters to generate a PWM signal. This function can manually assign the specified channel to set the PWM cycle.

Note: When setting PWM output from multiple output pins, all should use the same PWM period

---

Parameters

- base – Ctimer peripheral base address
- pwmPeriodChannel – Specify the channel to control the PWM period
- matchChannel – Match pin to be used to output the PWM signal
- pwmPeriod – PWM period match value
- pulsePeriod – Pulse width match value
- enableInt – Enable interrupt when the timer value reaches the match value of the PWM pulse, if it is 0 then no interrupt will be generated.

Returns

kStatus_Success on success kStatus_Fail If matchChannel is equal to pwmPeriodChannel; this channel is reserved to set the PWM cycle If PWM pulse width register value is larger than 0xFFFFFFFF.

status_t CTIMER_SetupPwm(CTIMER_Type *base, const *ctimer_match_t* pwmPeriodChannel, *ctimer_match_t* matchChannel, uint8_t dutyCyclePercent, uint32_t pwmFreq_Hz, uint32_t srcClock_Hz, bool enableInt)

Configures the PWM signal parameters.

Enables PWM mode on the match channel passed in and will then setup the match value and other match parameters to generate a PWM signal. This function can manually assign the specified channel to set the PWM cycle.

Note: When setting PWM output from multiple output pins, all should use the same PWM frequency. Please use CTIMER_SetupPwmPeriod to set up the PWM with high resolution.

Parameters

- base – Ctimer peripheral base address
- pwmPeriodChannel – Specify the channel to control the PWM period
- matchChannel – Match pin to be used to output the PWM signal
- dutyCyclePercent – PWM pulse width; the value should be between 0 to 100
- pwmFreq_Hz – PWM signal frequency in Hz
- srcClock_Hz – Timer counter clock in Hz
- enableInt – Enable interrupt when the timer value reaches the match value of the PWM pulse, if it is 0 then no interrupt will be generated.

static inline void CTIMER_UpdatePwmPulsePeriod(CTIMER_Type *base, *ctimer_match_t* matchChannel, uint32_t pulsePeriod)

Updates the pulse period of an active PWM signal.

Parameters

- base – Ctimer peripheral base address
- matchChannel – Match pin to be used to output the PWM signal
- pulsePeriod – New PWM pulse width match value

status_t CTIMER_UpdatePwmDutycycle(CTIMER_Type *base, const *ctimer_match_t* pwmPeriodChannel, *ctimer_match_t* matchChannel, uint8_t dutyCyclePercent)

Updates the duty cycle of an active PWM signal.

Note: Please use CTIMER_SetupPwmPeriod to update the PWM with high resolution. This function can manually assign the specified channel to set the PWM cycle.

Parameters

- base – Ctimer peripheral base address
- pwmPeriodChannel – Specify the channel to control the PWM period
- matchChannel – Match pin to be used to output the PWM signal
- dutyCyclePercent – New PWM pulse width; the value should be between 0 to 100

Returns

kStatus_Success on success kStatus_Fail If PWM pulse width register value is larger than 0xFFFFFFFF.

static inline void CTIMER_EnableInterrupts(CTIMER_Type *base, uint32_t mask)

Enables the selected Timer interrupts.

Parameters

- base – Ctimer peripheral base address
- mask – The interrupts to enable. This is a logical OR of members of the enumeration *ctimer_interrupt_enable_t*

static inline void CTIMER_DisableInterrupts(CTIMER_Type *base, uint32_t mask)

Disables the selected Timer interrupts.

Parameters

- base – Ctimer peripheral base address
- mask – The interrupts to enable. This is a logical OR of members of the enumeration *ctimer_interrupt_enable_t*

static inline uint32_t CTIMER_GetEnabledInterrupts(CTIMER_Type *base)

Gets the enabled Timer interrupts.

Parameters

- base – Ctimer peripheral base address

Returns

The enabled interrupts. This is the logical OR of members of the enumeration *ctimer_interrupt_enable_t*

static inline uint32_t CTIMER_GetStatusFlags(CTIMER_Type *base)

Gets the Timer status flags.

Parameters

- base – Ctimer peripheral base address

Returns

The status flags. This is the logical OR of members of the enumeration *ctimer_status_flags_t*

static inline void CTIMER_ClearStatusFlags(CTIMER_Type *base, uint32_t mask)

Clears the Timer status flags.

Parameters

- base – Ctimer peripheral base address
- mask – The status flags to clear. This is a logical OR of members of the enumeration *ctimer_status_flags_t*

static inline void CTIMER_StartTimer(CTIMER_Type *base)

Starts the Timer counter.

Parameters

- base – Ctimer peripheral base address

static inline void CTIMER_StopTimer(CTIMER_Type *base)

Stops the Timer counter.

Parameters

- base – Ctimer peripheral base address

FSL_CTIMER_DRIVER_VERSION

Version 2.3.6

enum _ctimer_capture_channel

List of Timer capture channels.

Values:

enumerator kCTIMER_Capture_0

Timer capture channel 0

enumerator kCTIMER_Capture_1
Timer capture channel 1

enumerator kCTIMER_Capture_3
Timer capture channel 3

enum _ctimer_capture_edge
List of capture edge options.
Values:

enumerator kCTIMER_Capture_RiseEdge
Capture on rising edge

enumerator kCTIMER_Capture_FallEdge
Capture on falling edge

enumerator kCTIMER_Capture_BothEdge
Capture on rising and falling edge

enum _ctimer_match
List of Timer match registers.
Values:

enumerator kCTIMER_Match_0
Timer match register 0

enumerator kCTIMER_Match_1
Timer match register 1

enumerator kCTIMER_Match_2
Timer match register 2

enumerator kCTIMER_Match_3
Timer match register 3

enum _ctimer_external_match
List of external match.
Values:

enumerator kCTIMER_External_Match_0
External match 0

enumerator kCTIMER_External_Match_1
External match 1

enumerator kCTIMER_External_Match_2
External match 2

enumerator kCTIMER_External_Match_3
External match 3

enum _ctimer_match_output_control
List of output control options.
Values:

enumerator kCTIMER_Output_NoAction
No action is taken

enumerator kCTIMER_Output_Clear
Clear the EM bit/output to 0

enumerator kCTIMER_Output_Set
Set the EM bit/output to 1

enumerator kCTIMER_Output_Toggle
Toggle the EM bit/output

enum _ctimer_timer_mode
List of Timer modes.
Values:

enumerator kCTIMER_TimerMode

enumerator kCTIMER_IncreaseOnRiseEdge

enumerator kCTIMER_IncreaseOnFallEdge

enumerator kCTIMER_IncreaseOnBothEdge

enum _ctimer_interrupt_enable
List of Timer interrupts.
Values:

enumerator kCTIMER_Match0InterruptEnable
Match 0 interrupt

enumerator kCTIMER_Match1InterruptEnable
Match 1 interrupt

enumerator kCTIMER_Match2InterruptEnable
Match 2 interrupt

enumerator kCTIMER_Match3InterruptEnable
Match 3 interrupt

enum _ctimer_status_flags

List of Timer flags.

Values:

enumerator kCTIMER_Match0Flag

Match 0 interrupt flag

enumerator kCTIMER_Match1Flag

Match 1 interrupt flag

enumerator kCTIMER_Match2Flag

Match 2 interrupt flag

enumerator kCTIMER_Match3Flag

Match 3 interrupt flag

enum ctimer_callback_type_t

Callback type when registering for a callback. When registering a callback an array of function pointers is passed the size could be 1 or 8, the callback type will tell that.

Values:

enumerator kCTIMER_SingleCallback

Single Callback type where there is only one callback for the timer. based on the status flags different channels needs to be handled differently

enumerator kCTIMER_MultipleCallback

Multiple Callback type where there can be 8 valid callbacks, one per channel. for both match/capture

typedef enum *_ctimer_capture_channel* ctimer_capture_channel_t

List of Timer capture channels.

typedef enum *_ctimer_capture_edge* ctimer_capture_edge_t

List of capture edge options.

typedef enum *_ctimer_match* ctimer_match_t

List of Timer match registers.

typedef enum *_ctimer_external_match* ctimer_external_match_t

List of external match.

typedef enum *_ctimer_match_output_control* ctimer_match_output_control_t

List of output control options.

typedef enum *_ctimer_timer_mode* ctimer_timer_mode_t

List of Timer modes.

typedef enum *_ctimer_interrupt_enable* ctimer_interrupt_enable_t

List of Timer interrupts.

typedef enum *_ctimer_status_flags* ctimer_status_flags_t

List of Timer flags.

typedef void (*ctimer_callback_t)(uint32_t flags)

typedef struct *_ctimer_match_config* ctimer_match_config_t

Match configuration.

This structure holds the configuration settings for each match register.

typedef struct *_ctimer_config* ctimer_config_t

Timer configuration structure.

This structure holds the configuration settings for the Timer peripheral. To initialize this structure to reasonable defaults, call the *CTIMER_GetDefaultConfig()* function and pass a pointer to the configuration structure instance.

The configuration structure can be made constant so as to reside in flash.

void CTIMER_SetupMatch(CTIMER_Type *base, *ctimer_match_t* matchChannel, const *ctimer_match_config_t* *config)

Setup the match register.

User configuration is used to setup the match value and action to be taken when a match occurs.

Parameters

- base – Ctimer peripheral base address
- matchChannel – Match register to configure
- config – Pointer to the match configuration structure

uint32_t CTIMER_GetOutputMatchStatus(CTIMER_Type *base, uint32_t matchChannel)

Get the status of output match.

This function gets the status of output MAT, whether or not this output is connected to a pin. This status is driven to the MAT pins if the match function is selected via IOCON. 0 = LOW. 1 = HIGH.

Parameters

- base – Ctimer peripheral base address
- matchChannel – External match channel, user can obtain the status of multiple match channels at the same time by using the logic of "|" enumeration *ctimer_external_match_t*

Returns

The mask of external match channel status flags. Users need to use the _ctimer_external_match type to decode the return variables.

void CTIMER_SetupCapture(CTIMER_Type *base, *ctimer_capture_channel_t* capture, *ctimer_capture_edge_t* edge, bool enableInt)

Setup the capture.

Parameters

- base – Ctimer peripheral base address
- capture – Capture channel to configure
- edge – Edge on the channel that will trigger a capture

- enableInt – Flag to enable channel interrupts, if enabled then the registered call back is called upon capture

static inline uint32_t CTIMER_GetTimerCountValue(CTIMER_Type *base)

Get the timer count value from TC register.

Parameters

- base – Ctimer peripheral base address.

Returns

return the timer count value.

void CTIMER_RegisterCallBack(CTIMER_Type *base, *ctimer_callback_t* *cb_func, *ctimer_callback_type_t* cb_type)

Register callback.

This function configures CTimer Callback in following modes:

- Single Callback: cb_func should be pointer to callback function pointer For example: ctimer_callback_t ctimer_callback = pwm_match_callback; CTIMER_RegisterCallBack(CTIMER, &ctimer_callback, kCTIMER_SingleCallback);
- Multiple Callback: cb_func should be pointer to array of callback function pointers Each element corresponds to Interrupt Flag in IR register. For example: ctimer_callback_t ctimer_callback_table[] = { ctimer_match0_callback, NULL, NULL, ctimer_match3_callback, NULL, NULL, NULL, NULL}; CTIMER_RegisterCallBack(CTIMER, &ctimer_callback_table[0], kCTIMER_MultipleCallback);

Parameters

- base – Ctimer peripheral base address
- cb_func – Pointer to callback function pointer
- cb_type – callback function type, singular or multiple

static inline void CTIMER_Reset(CTIMER_Type *base)

Reset the counter.

The timer counter and prescale counter are reset on the next positive edge of the APB clock.

Parameters

- base – Ctimer peripheral base address

static inline void CTIMER_SetPrescale(CTIMER_Type *base, uint32_t prescale)

Setup the timer prescale value.

Specifies the maximum value for the Prescale Counter.

Parameters

- base – Ctimer peripheral base address
- prescale – Prescale value

static inline uint32_t CTIMER_GetCaptureValue(CTIMER_Type *base, *ctimer_capture_channel_t* capture)

Get capture channel value.

Get the counter/timer value on the corresponding capture channel.

Parameters

- base – Ctimer peripheral base address
- capture – Select capture channel

Returns
The timer count capture value.

static inline void CTIMER_EnableResetMatchChannel(CTIMER_Type *base, *ctimer_match_t* match, bool enable)

Enable reset match channel.

Set the specified match channel reset operation.

Parameters

- base – Ctimer peripheral base address
- match – match channel used
- enable – Enable match channel reset operation.

static inline void CTIMER_EnableStopMatchChannel(CTIMER_Type *base, *ctimer_match_t* match, bool enable)

Enable stop match channel.

Set the specified match channel stop operation.

Parameters

- base – Ctimer peripheral base address.
- match – match channel used.
- enable – Enable match channel stop operation.

static inline void CTIMER_EnableMatchChannelReload(CTIMER_Type *base, *ctimer_match_t* match, bool enable)

Enable reload channel falling edge.

Enable the specified match channel reload match shadow value.

Parameters

- base – Ctimer peripheral base address.
- match – match channel used.
- enable – Enable .

static inline void CTIMER_EnableRisingEdgeCapture(CTIMER_Type *base, *ctimer_capture_channel_t* capture, bool enable)

Enable capture channel rising edge.

Sets the specified capture channel for rising edge capture.

Parameters

- base – Ctimer peripheral base address.
- capture – capture channel used.
- enable – Enable rising edge capture.

static inline void CTIMER_EnableFallingEdgeCapture(CTIMER_Type *base, *ctimer_capture_channel_t* capture, bool enable)

Enable capture channel falling edge.

Sets the specified capture channel for falling edge capture.

Parameters

- base – Ctimer peripheral base address.

- capture – capture channel used.
- enable – Enable falling edge capture.

static inline void CTIMER_SetShadowValue(CTIMER_Type *base, *ctimer_match_t* match, uint32_t matchvalue)

Set the specified match shadow channel.

Parameters

- base – Ctimer peripheral base address.
- match – match channel used.
- matchvalue – Reload the value of the corresponding match register.

struct __ctimer_match_config

#include <fsl_ctimer.h> Match configuration.

This structure holds the configuration settings for each match register.

Public Members

uint32_t matchValue

This is stored in the match register

bool enableCounterReset

true: Match will reset the counter false: Match will not reser the counter

bool enableCounterStop

true: Match will stop the counter false: Match will not stop the counter

ctimer_match_output_control_t outControl

Action to be taken on a match on the EM bit/output

bool outPinInitState

Initial value of the EM bit/output

bool enableInterrupt

true: Generate interrupt upon match false: Do not generate interrupt on match

struct __ctimer_config

#include <fsl_ctimer.h> Timer configuration structure.

This structure holds the configuration settings for the Timer peripheral. To initialize this structure to reasonable defaults, call the *CTIMER_GetDefaultConfig()* function and pass a pointer to the configuration structure instance.

The configuration structure can be made constant so as to reside in flash.

Public Members

ctimer_timer_mode_t mode

Timer mode

ctimer_capture_channel_t input

Input channel to increment the timer, used only in timer modes that rely on this input signal to increment TC

uint32_t prescale

Prescale value

2.6 DAC: Digital-to-Analog Converter Driver

void DAC_Init(LPDAC_Type *base, const *dac_config_t* *config)

Initialize the DAC module with common configuartion.

The clock will be enabled in this function.

Parameters

- base – DAC peripheral base address.
- config – Pointer to configuration structure.

void DAC_GetDefaultConfig(*dac_config_t* *config)

Get the default settings for initialization's configuration.

This function initializes the user configuration structure to a default value. The default values are:

```
config->fifoWatermarkLevel = 0U;
config->fifoTriggerMode = kDAC_FIFOTriggerByHardwareMode;
config->fifoWorkMode = kDAC_FIFODisabled;
config->enableLowPowerMode = false;
config->referenceVoltageSource = kDAC_ReferenceVoltageSourceAlt1;
```

Parameters

- config – Pointer to configuration structure.

void DAC_Deinit(LPDAC_Type *base)

De-initialize the DAC module.

The clock will be disabled in this function.

Parameters

- base – DAC peripheral base address.

static inline void DAC_SetReset(LPDAC_Type *base, uint32_t mask)

Assert the reset control to part hardware.

This function is to assert the reset control to part hardware. Responding part hardware would remain reset untill cleared by software.

Parameters

- base – DAC peripheral base address.
- mask – The reset control mask, see to _dac_reset_control_t.

static inline void DAC_ClearReset(LPDAC_Type *base, uint32_t mask)

Clear the reset control to part hardware.

This function is to clear the reset control to part hardware. Responding part hardware would work after the reset control is cleared by software.

Parameters

- base – DAC peripheral base address.
- mask – The reset control mask, see to _dac_reset_control_t.

static inline void DAC_Enable(LPDAC_Type *base, bool enable)

Enable the DAC hardware system or not.

This function is to start the Programmable Reference Generator operation or not.

Parameters

- base – DAC peripheral base address.
- enable – Assertion of indicated event.

static inline void DAC_EnableInterrupts(LPDAC_Type *base, uint32_t mask)

Enable the interrupts.

Parameters

- base – DAC peripheral base address.
- mask – Mask value of indicated interrupt events. See to _dac_interrupt_enable.

static inline void DAC_DisableInterrupts(LPDAC_Type *base, uint32_t mask)

Disable the interrupts.

Parameters

- base – DAC peripheral base address.
- mask – Mask value of indicated interrupt events. See to _dac_interrupt_enable.

static inline void DAC_EnableDMA(LPDAC_Type *base, uint32_t mask, bool enable)

Enable the DMA switchers or not.

Parameters

- base – DAC peripheral base address.
- mask – Mask value of indicated DMA requeset. See to _dac_dma_enable.
- enable – Enable the DMA or not.

static inline uint32_t DAC_GetStatusFlags(LPDAC_Type *base)

Get status flags of DAC module.

Parameters

- base – DAC peripheral base address.

Returns

Mask value of status flags. See to _dac_status_flags.

static inline void DAC_ClearStatusFlags(LPDAC_Type *base, uint32_t flags)

Clear status flags of DAC module.

Parameters

- base – DAC peripheral base address.
- flags – Mask value of status flags to be cleared. See to _dac_status_flags.

static inline void DAC_SetData(LPDAC_Type *base, uint32_t value)

Set data into the entry of FIFO buffer.

Parameters

- base – DAC peripheral base address.
- value – Setting value into FIFO buffer.

static inline uint32_t DAC_GetFIFOWritePointer(LPDAC_Type *base)

Get the value of the FIFO write pointer.

Parameters

- base – DAC peripheral base address.

Returns

Current value of the FIFO write pointer.

static inline uint32_t DAC_GetFIFOReadPointer(LPDAC_Type *base)

Get the value of the FIFO read pointer.

Parameters

- base – DAC peripheral base address.

Returns

Current value of the FIFO read pointer.

static inline void DAC_DoSoftwareTriggerFIFO(LPDAC_Type *base)

Do software trigger to FIFO when in software mode.

Parameters

- base – DAC peripheral base address.

FSL_DAC_DRIVER_VERSION

DAC driver version 2.2.0.

DAC reset control.

Values:

enumerator kDAC_ResetFIFO

Resets the FIFO pointers and flags.

enumerator kDAC_ResetLogic

Resets all DAC registers and internal logic.

DAC interrupts.

Values:

enumerator kDAC_FIFOFullInterruptEnable

FIFO full interrupt enable.

enumerator kDAC_FIFOEmptyInterruptEnable

FIFO empty interrupt enable.

enumerator kDAC_FIFOWatermarkInterruptEnable

FIFO watermark interrupt enable.

enumerator kDAC_SwingBackInterruptEnable

Swing back one cycle complete interrupt enable.

enumerator kDAC_FIFOOverflowInterruptEnable

FIFO overflow interrupt enable.

enumerator kDAC_FIFOUnderflowInterruptEnable

FIFO underflow interrupt enable.

enumerator kDAC_PeriodTriggerCompleteInterruptEnable

Period trigger mode conversion complete interrupt enable

DAC DMA switchers.

Values:

enumerator kDAC_FIFOEmptyDMAEnable

FIFO empty DMA enable.

enumerator kDAC_FIFOWatermarkDMAEnable

FIFO watermark DMA enable.

DAC status flags.

Values:

enumerator kDAC_FIFOUnderflowFlag

This flag means that there is a new trigger after the buffer is empty. The FIFO read pointer will not increase in this case and the data sent to DAC analog conversion will not changed. This flag is cleared by writing a 1 to it.

enumerator kDAC_FIFOOverflowFlag

This flag indicates that data is intended to write into FIFO after the buffer is full. The writer pointer will not increase in this case. The extra data will not be written into the FIFO. This flag is cleared by writing a 1 to it.

enumerator kDAC_FIFOSwingBackFlag

This flag indicates that the DAC has completed one period of conversion in swing back mode. It means that the read pointer has increased to the top (write pointer) once and then decreased to zero once. For example, after three data is written to FIFO, the writer pointer is now 3. Then, if continually triggered, the read pointer will swing like: 0-1-2-1-0-1-2-, and so on. After the fourth trigger, the flag is set. This flag is cleared by writing a 1 to it.

enumerator kDAC_FIFOWatermarkFlag

This field is set if the remaining data in FIFO is less than or equal to the setting value of wartermark. By writing data into FIFO by DMA or CPU, this flag is cleared automatically when the data in FIFO is more than the setting value of watermark.

enumerator kDAC_FIFOEmptyFlag

FIFO empty flag.

enumerator kDAC_FIFOFullFlag

FIFO full flag.

enumerator kDAC_PeriodTriggerCompleteFlag

Period trigger mode conversion complete flag.

enum _dac_fifo_trigger_mode

DAC FIFO trigger mode.

Values:

enumerator kDAC_FIFOTriggerByHardwareMode

Buffer would be triggered by hardware.

enumerator kDAC_FIFOTriggerBySoftwareMode

Buffer would be triggered by software.

enum _dac_fifo_work_mode

DAC FIFO work mode.

Values:

enumerator kDAC_FIFODisabled

FIFO mode is disabled and buffer mode is enabled. Any data written to DATA[DATA] goes to buffer then goes to conversion.

enumerator kDAC_FIFOWorkAsNormalMode

FIFO mode is enabled. Data will be first read from FIFO to buffer then goes to conversion.

enumerator kDAC_FIFOWorkAsSwingMode

In swing mode, the read pointer swings between the writer pointer and zero. That is, the trigger increases the read pointer till reach the writer pointer and decreases the read pointer till zero, and so on. The FIFO empty/full/watermark flag will not update during swing back mode.

enumerator kDAC_FIFOWorkAsPeriodTriggerMode

In periodic trigger mode, user only needs to send the first trigger. Then after every [PTG_PERIOD+1] RCLK cycles, DAC will be automatically triggered by internal trigger. There will be [PTG_NUM] internal triggers, thus in total [PTG_NUM+1] conversions including the first trigger sent by user. User can terminate the current conversion queue by clearing the GCR[PTGEN] bit. Then, after the current conversion is completed, the conversion is terminated and the PTGCOCO flag is set. If PCR[PTG_NUM] is set to zero, there will be infinite triggers following the first hardware/software trigger, until the GCR[PTGEN] is cleared by software. In any case, the conversion can be terminated by FIFORST/SWRST.

enumerator kDAC_FIFOWorkAsPeriodTriggerAndSwingMode

Periodically trigger DAC and swing back.

enum _dac_reference_voltage_source

DAC reference voltage source.

Values:

enumerator kDAC_ReferenceVoltageSourceAlt1

The DAC selects VREFH_INT as the reference voltage.

enumerator kDAC_ReferenceVoltageSourceAlt2

The DAC selects VREFH_EXT as the reference voltage.

enum _dac_reference_current_source

Values:

enumerator kDAC_ReferenceCurrentSourcePtat

enumerator kDAC_ReferenceCurrentSourceInternal

enumerator kDAC_ReferenceCurrentSourceZtc

enum _dac_reference_current_trim

Values:

enumerator kDAC_ReferenceCurrentTrimMinus25Percent

Internal current value -25%.

enumerator kDAC_ReferenceCurrentTrimMinus125Percent

Internal current value -12.5%.

enumerator kDAC_ReferenceCurrentTrimTypical

Typical internal current value.

enumerator kDAC_ReferenceCurrentTrimPlus125Percent

Internal current value +12.5%.

enumerator kDAC_ReferenceCurrentTrimPlus25Percent

Internal current value +25%.

typedef enum *_dac_fifo_trigger_mode* dac_fifo_trigger_mode_t

DAC FIFO trigger mode.

typedef enum *_dac_fifo_work_mode* dac_fifo_work_mode_t

DAC FIFO work mode.

typedef enum *_dac_reference_voltage_source* dac_reference_voltage_source_t

DAC reference voltage source.

typedef enum *_dac_reference_current_source* dac_reference_current_source_t

typedef enum *_dac_reference_current_trim* dac_reference_current_trim_t

typedef struct *_dac_config* dac_config_t

DAC configuration structure.

struct _dac_config

#include <fsl_dac.h> DAC configuration structure.

Public Members

uint32_t fifoWatermarkLevel

FIFO's watermark, the max value can be the hardware FIFO size.

dac_fifo_trigger_mode_t fifoTriggerMode

Select the trigger mode for FIFO.

dac_fifo_work_mode_t fifoWorkMode

Select the work mode for FIFO.

bool enableOpampBuffer

Opamp is used as buffer.

bool enableAnalogOutputBufferBypass

Bypass the DAC analog output buffer.

bool enableLowerLowPowerMode

Enable the lower low power mode.

uint32_t periodicTriggerNumber

There will be 'periodicTriggerNumber' internal triggers following the first hardware/software trigger. So there will be 'periodicTriggerNumber + 1' conversions in total. If set to zero, there will be infinite triggers following the first hw/sw trigger, until the GCR[PTGEN] is cleared.

uint32_t periodicTriggerWidth

Control the periodic trigger frequency. There will be 'periodicTriggerWidth + 1' RCLK cycles between each periodic trigger. The periodic trigger frequency should be configured to not larger than the analog conversion speed.

uint32_t syncTime

RCLK cycles before data latch. accessible range is 0-15. It is used to configure the DAC sync cycles which is helpful to reduce glitch on the output. The sync time is (LATCH_CYC+1) RCLK cycles. User should configure this register according to the RCLK frequency. The recommended sync time is at least 40ns.

dac_reference_current_source_t referenceCurrentSource

Select the internal reference current source.

dac_reference_current_trim_t referenceCurrentTrim

Select the internal reference current trim.

dac_reference_voltage_source_t referenceVoltageSource

Select the reference voltage source.

2.7 eDMA: Enhanced Direct Memory Access (eDMA) Controller Driver

void EDMA_Init(*EDMA_Type* *base, const *edma_config_t* *config)

Initializes the eDMA peripheral.

This function ungates the eDMA clock and configures the eDMA peripheral according to the configuration structure. All emda enabled request will be cleared in this function.

Note: This function enables the minor loop map feature.

Parameters

- base – eDMA peripheral base address.
- config – A pointer to the configuration structure, see "edma_config_t".

void EDMA_Deinit(*EDMA_Type* *base)

Deinitializes the eDMA peripheral.

This function gates the eDMA clock.

Parameters

- base – eDMA peripheral base address.

void EDMA_InstallTCD(*EDMA_Type* *base, uint32_t channel, *edma_tcd_t* *tcd)

Push content of TCD structure into hardware TCD register.

Parameters

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

void EDMA_GetDefaultConfig(*edma_config_t* *config)

Gets the eDMA default configuration structure.

This function sets the configuration structure to default values. The default configuration is set to the following values.

```
config.enableContinuousLinkMode = false;
config.enableHaltOnError = true;
config.enableRoundRobinArbitration = false;
config.enableDebugMode = false;
```

Parameters

- config – A pointer to the eDMA configuration structure.

void EDMA_InitChannel(*EDMA_Type* *base, uint32_t channel, *edma_channel_config_t* *channelConfig)

EDMA Channel initialization.

Parameters

- base – eDMA4 peripheral base address.
- channel – eDMA4 channel number.
- channelConfig – pointer to user's eDMA4 channel config structure, see edma_channel_config_t for detail.

static inline void EDMA_SetChannelMemoryAttribute(*EDMA_Type* *base, uint32_t channel, *edma_channel_memory_attribute_t* writeAttribute, *edma_channel_memory_attribute_t* readAttribute)

Set channel memory attribute.

Parameters

- base – eDMA4 peripheral base address.
- channel – eDMA4 channel number.
- writeAttribute – Attributes associated with a write transaction.
- readAttribute – Attributes associated with a read transaction.

static inline void EDMA_SetChannelSignExtension(*EDMA_Type* *base, uint32_t channel, uint8_t position)

Set channel sign extension.

Parameters

- base – eDMA4 peripheral base address.
- channel – eDMA4 channel number.
- position – A non-zero value specifing the sign extend bit position. If 0, sign extension is disabled.

static inline void EDMA_SetChannelSwapSize(*EDMA_Type* *base, uint32_t channel, *edma_channel_swap_size_t* swapSize)

Set channel swap size.

Parameters

- base – eDMA4 peripheral base address.
- channel – eDMA4 channel number.
- swapSize – Swap occurs with respect to the specified transfer size. If 0, swap is disabled.

static inline void EDMA_SetChannelAccessType(*EDMA_Type* *base, uint32_t channel, *edma_channel_access_type_t* channelAccessType)

Set channel access type.

Parameters

- base – eDMA4 peripheral base address.
- channel – eDMA4 channel number.
- channelAccessType – eDMA4's transactions type on the system bus when the channel is active.

static inline void EDMA_SetChannelMux(*EDMA_Type* *base, uint32_t channel, uint32_t channelRequestSource)

Set channel request source.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- channelRequestSource – eDMA hardware service request source for the channel. User need to use the dma_request_source_t type as the input parameter. Note that devices may use other enum type to express dma request source and User can fined it in SOC header or fsl_edma_soc.h.

static inline uint32_t EDMA_GetChannelSystemBusInformation(*EDMA_Type* *base, uint32_t channel)

Gets the channel identification and attribute information on the system bus interface.

Parameters

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

Returns

The mask of the channel system bus information. Users need to use the _edma_channel_sys_bus_info type to decode the return variables.

static inline void EDMA_EnableChannelMasterIDReplication(*EDMA_Type* *base, uint32_t channel, bool enable)

Set channel master ID replication.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- enable – true is enable, false is disable.

static inline void EDMA_SetChannelProtectionLevel(*EDMA_Type* *base, uint32_t channel, *edma_channel_protection_level_t* level)

Set channel security level.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- level – security level.

void EDMA_ResetChannel(*EDMA_Type* *base, uint32_t channel)

Sets all TCD registers to default values.

This function sets TCD registers for this channel to default values.

Note: This function must not be called while the channel transfer is ongoing or it causes unpredictable results.

Note: This function enables the auto stop request feature.

Parameters

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

void EDMA_SetTransferConfig(*EDMA_Type* *base, uint32_t channel, const *edma_transfer_config_t* *config, *edma_tcd_t* *nextTcd)

Configures the eDMA transfer attribute.

This function configures the transfer attribute, including source address, destination address, transfer size, address offset, and so on. It also configures the scatter gather feature if the user supplies the TCD address. Example:

```
edma_transfer_t config;
edma_tcd_t tcd;
config.srcAddr = ..;
config.destAddr = ..;
...
EDMA_SetTransferConfig(DMA0, channel, &config, &stcd);
```

Note: If nextTcd is not NULL, it means scatter gather feature is enabled and DREQ bit is cleared in the previous transfer configuration, which is set in the eDMA_ResetChannel.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- config – Pointer to eDMA transfer configuration structure.
- nextTcd – Point to TCD structure. It can be NULL if users do not want to enable scatter/gather feature.

void EDMA_SetMinorOffsetConfig(*EDMA_Type* *base, uint32_t channel, const *edma_minor_offset_config_t* *config)

Configures the eDMA minor offset feature.

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

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- config – A pointer to the minor offset configuration structure.

void EDMA_SetChannelPreemptionConfig(*EDMA_Type* *base, uint32_t channel, const *edma_channel_Preemption_config_t* *config)

Configures the eDMA channel preemption feature.

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

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number
- config – A pointer to the channel preemption configuration structure.

void EDMA_SetChannelLink(*EDMA_Type* *base, uint32_t channel, *edma_channel_link_type_t* type, uint32_t linkedChannel)

Sets the channel link for the eDMA transfer.

This function configures either the minor link or the major link mode. The minor link means that the channel link is triggered every time CITER decreases by 1. The major link means that the channel link is triggered when the CITER is exhausted.

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

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- type – A channel link type, which can be one of the following:
  - kEDMA_LinkNone
  - kEDMA_MinorLink
  - kEDMA_MajorLink
- linkedChannel – The linked channel number.

void EDMA_SetBandWidth(*EDMA_Type* *base, uint32_t channel, *edma_bandwidth_t* bandWidth)

Sets the bandwidth for the eDMA transfer.

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

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- bandWidth – A bandwidth setting, which can be one of the following:
  - kEDMABandwidthStallNone
  - kEDMABandwidthStall4Cycle
  - kEDMABandwidthStall8Cycle

void EDMA_SetModulo(*EDMA_Type* *base, uint32_t channel, *edma_modulo_t* srcModulo, *edma_modulo_t* destModulo)

Sets the source modulo and the destination modulo for the eDMA transfer.

This function defines a specific address range specified to be the value after (SADDR + SOFF)/(DADDR + DOFF) calculation is performed or the original register value. It provides the ability to implement a circular data queue easily.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- srcModulo – A source modulo value.
- destModulo – A destination modulo value.

static inline void EDMA_EnableAsyncRequest(*EDMA_Type* *base, uint32_t channel, bool enable)

Enables an async request for the eDMA transfer.

Parameters

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

static inline void EDMA_EnableAutoStopRequest(*EDMA_Type* *base, uint32_t channel, bool enable)

Enables an auto stop request for the eDMA transfer.

If enabling the auto stop request, the eDMA hardware automatically disables the hardware channel request.

Parameters

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

void EDMA_EnableChannelInterrupts(*EDMA_Type* *base, uint32_t channel, uint32_t mask)

Enables the interrupt source for the eDMA transfer.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- mask – The mask of interrupt source to be set. Users need to use the defined edma_interrupt_enable_t type.

void EDMA_DisableChannelInterrupts(*EDMA_Type* *base, uint32_t channel, uint32_t mask)

Disables the interrupt source for the eDMA transfer.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- mask – The mask of the interrupt source to be set. Use the defined edma_interrupt_enable_t type.

void EDMA_SetMajorOffsetConfig(*EDMA_Type* *base, uint32_t channel, int32_t sourceOffset, int32_t destOffset)

Configures the eDMA channel TCD major offset feature.

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

Parameters

- base – eDMA peripheral base address.
- channel – edma channel number.
- sourceOffset – source address offset will be applied to source address after major loop done.
- destOffset – destination address offset will be applied to source address after major loop done.

void EDMA_ConfigChannelSoftwareTCD(*edma_tcd_t* *tcd, const *edma_transfer_config_t* *transfer)

Sets TCD fields according to the user's channel transfer configuration structure, *edma_transfer_config_t*.

@Note This API only supports EDMA4 TCD type. It can be used to support all types with extension API *EDMA_ConfigChannelSoftwareTCDExt*

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

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

Note: This function enables the auto stop request feature.

Parameters

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

void EDMA_TcdReset(*edma_tcd_t* *tcd)

Sets all fields to default values for the TCD structure.

@Note This API only supports EDMA4 TCD type. It can be used to support all types with extension API *EDMA_TcdResetExt*

This function sets all fields for this TCD structure to default value.

Note: This function enables the auto stop request feature.

Parameters

- tcd – Pointer to the TCD structure.

void EDMA_TcdSetTransferConfig(*edma_tcd_t* *tcd, const *edma_transfer_config_t* *config, *edma_tcd_t* *nextTcd)

Configures the eDMA TCD transfer attribute.

@Note This API only supports EDMA4 TCD type. It can be used to support all types with extension API *EDMA_TcdSetTransferConfigExt*

The TCD is a transfer control descriptor. The content of the TCD is the same as the hardware TCD registers. The TCD is used in the scatter-gather mode. This function configures the TCD transfer attribute, including source address, destination address, transfer size, address offset, and so on. It also configures the scatter gather feature if the user supplies the next TCD address. Example:

```
edma_transfer_t config = {
...
}
edma_tcd_t tcd __aligned(32);
edma_tcd_t nextTcd __aligned(32);
EDMA_TcdSetTransferConfig(&tcd, &config, &nextTcd);
```

Note: TCD address should be 32 bytes aligned or it causes an eDMA error.

Note: If the nextTcd is not NULL, the scatter gather feature is enabled and DREQ bit is cleared in the previous transfer configuration, which is set in the EDMA_TcdReset.

Parameters

- tcd – Pointer to the TCD structure.
- config – Pointer to eDMA transfer configuration structure.
- nextTcd – Pointer to the next TCD structure. It can be NULL if users do not want to enable scatter/gather feature.

void EDMA_TcdSetMinorOffsetConfig(*edma_tcd_t* *tcd, const *edma_minor_offset_config_t* *config)

Configures the eDMA TCD minor offset feature.

@Note This API only supports EDMA4 TCD type. It can be used to support all types with extension API *EDMA_TcdSetMinorOffsetConfigExt*

A minor offset is a signed-extended value added to the source address or a destination address after each minor loop.

Parameters

- tcd – A point to the TCD structure.
- config – A pointer to the minor offset configuration structure.

void EDMA_TcdSetChannelLink(*edma_tcd_t* *tcd, *edma_channel_link_type_t* type, uint32_t linkedChannel)

Sets the channel link for the eDMA TCD.

@Note This API only supports EDMA4 TCD type. It can be used to support all types with extension API *EDMA_TcdSetChannelLinkExt*

This function configures either a minor link or a major link. The minor link means the channel link is triggered every time CITER decreases by 1. The major link means that the channel link is triggered when the CITER is exhausted.

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

Parameters

- tcd – Point to the TCD structure.
- type – Channel link type, it can be one of:
  - kEDMA_LinkNone
  - kEDMA_MinorLink
  - kEDMA_MajorLink
- linkedChannel – The linked channel number.

static inline void EDMA_TcdSetBandWidth(*edma_tcd_t* *tcd, *edma_bandwidth_t* bandWidth)

Sets the bandwidth for the eDMA TCD.

@Note This API only supports EDMA4 TCD type. It can be used to support all types with extension API *EDMA_TcdSetBandWidthExt*

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

Parameters

- tcd – A pointer to the TCD structure.
- bandWidth – A bandwidth setting, which can be one of the following:
  - kEDMABandwidthStallNone
  - kEDMABandwidthStall4Cycle
  - kEDMABandwidthStall8Cycle

void EDMA_TcdSetModulo(*edma_tcd_t* *tcd, *edma_modulo_t* srcModulo, *edma_modulo_t* destModulo)

Sets the source modulo and the destination modulo for the eDMA TCD.

@Note This API only supports EDMA4 TCD type. It can be used to support all types with extension API *EDMA_TcdSetModuloExt*

This function defines a specific address range specified to be the value after (SADDR + SOFF)/(DADDR + DOFF) calculation is performed or the original register value. It provides the ability to implement a circular data queue easily.

Parameters

- tcd – A pointer to the TCD structure.
- srcModulo – A source modulo value.
- destModulo – A destination modulo value.

static inline void EDMA_TcdEnableAutoStopRequest(*edma_tcd_t* *tcd, bool enable)

Sets the auto stop request for the eDMA TCD.

@Note This API only supports EDMA4 TCD type. It can be used to support all types with extension API *EDMA_TcdEnableAutoStopRequestExt*

If enabling the auto stop request, the eDMA hardware automatically disables the hardware channel request.

Parameters

- tcd – A pointer to the TCD structure.
- enable – The command to enable (true) or disable (false).

void EDMA_TcdEnableInterrupts(*edma_tcd_t* *tcd, uint32_t mask)

Enables the interrupt source for the eDMA TCD.

@Note This API only supports EDMA4 TCD type. It can be used to support all types with extension API *EDMA_TcdEnableInterruptsExt*

Parameters

- tcd – Point to the TCD structure.
- mask – The mask of interrupt source to be set. Users need to use the defined edma_interrupt_enable_t type.

void EDMA_TcdDisableInterrupts(*edma_tcd_t* *tcd, uint32_t mask)

Disables the interrupt source for the eDMA TCD.

@Note This API only supports EDMA4 TCD type. It can be used to support all types with extension API *EDMA_TcdDisableInterruptsExt*

Parameters

- tcd – Point to the TCD structure.
- mask – The mask of interrupt source to be set. Users need to use the defined edma_interrupt_enable_t type.

void EDMA_TcdSetMajorOffsetConfig(*edma_tcd_t* *tcd, int32_t sourceOffset, int32_t destOffset)

Configures the eDMA TCD major offset feature.

@Note This API only supports EDMA4 TCD type. It can be used to support all types with extension API *EDMA_TcdSetMajorOffsetConfigExt*

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

Parameters

- tcd – A point to the TCD structure.
- sourceOffset – source address offset wiil be applied to source address after major loop done.
- destOffset – destination address offset will be applied to source address after major loop done.

void EDMA_ConfigChannelSoftwareTCDExt(*EDMA_Type* *base, *edma_tcd_t* *tcd, const *edma_transfer_config_t* *transfer)

Sets TCD fields according to the user's channel transfer configuration structure, *edma_transfer_config_t*.

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

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

Note: This function enables the auto stop request feature.

Parameters

- base – eDMA peripheral base address.
- tcd – Pointer to the TCD structure.
- transfer – channel transfer configuration pointer.

void EDMA_TcdResetExt(*EDMA_Type* *base, *edma_tcd_t* *tcd)

Sets all fields to default values for the TCD structure.

This function sets all fields for this TCD structure to default value.

Note: This function enables the auto stop request feature.

Parameters

- base – eDMA peripheral base address.
- tcd – Pointer to the TCD structure.

void EDMA_TcdSetTransferConfigExt(*EDMA_Type* *base, *edma_tcd_t* *tcd, const *edma_transfer_config_t* *config, *edma_tcd_t* *nextTcd)

Configures the eDMA TCD transfer attribute.

The TCD is a transfer control descriptor. The content of the TCD is the same as the hardware TCD registers. The TCD is used in the scatter-gather mode. This function configures the

TCD transfer attribute, including source address, destination address, transfer size, address offset, and so on. It also configures the scatter gather feature if the user supplies the next TCD address. Example:

```
edma_transfer_t config = {
...
}
edma_tcd_t tcd __aligned(32);
edma_tcd_t nextTcd __aligned(32);
EDMA_TcdSetTransferConfig(&tcd, &config, &nextTcd);
```

Note: TCD address should be 32 bytes aligned or it causes an eDMA error.

Note: If the nextTcd is not NULL, the scatter gather feature is enabled and DREQ bit is cleared in the previous transfer configuration, which is set in the EDMA_TcdReset.

Parameters

- base – eDMA peripheral base address.
- tcd – Pointer to the TCD structure.
- config – Pointer to eDMA transfer configuration structure.
- nextTcd – Pointer to the next TCD structure. It can be NULL if users do not want to enable scatter/gather feature.

void EDMA_TcdSetMinorOffsetConfigExt(*EDMA_Type* *base, *edma_tcd_t* *tcd, const *edma_minor_offset_config_t* *config)

Configures the eDMA TCD minor offset feature.

A minor offset is a signed-extended value added to the source address or a destination address after each minor loop.

Parameters

- base – eDMA peripheral base address.
- tcd – A point to the TCD structure.
- config – A pointer to the minor offset configuration structure.

void EDMA_TcdSetChannelLinkExt(*EDMA_Type* *base, *edma_tcd_t* *tcd, *edma_channel_link_type_t* type, uint32_t linkedChannel)

Sets the channel link for the eDMA TCD.

This function configures either a minor link or a major link. The minor link means the channel link is triggered every time CITER decreases by 1. The major link means that the channel link is triggered when the CITER is exhausted.

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

Parameters

- base – eDMA peripheral base address.
- tcd – Point to the TCD structure.
- type – Channel link type, it can be one of:

  - kEDMA_LinkNone
  - kEDMA_MinorLink
  - kEDMA_MajorLink
- linkedChannel – The linked channel number.

static inline void EDMA_TcdSetBandWidthExt(*EDMA_Type* *base, *edma_tcd_t* *tcd, *edma_bandwidth_t* bandWidth)

Sets the bandwidth for the eDMA TCD.

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

Parameters

- base – eDMA peripheral base address.
- tcd – A pointer to the TCD structure.
- bandWidth – A bandwidth setting, which can be one of the following:
  - kEDMABandwidthStallNone
  - kEDMABandwidthStall4Cycle
  - kEDMABandwidthStall8Cycle

void EDMA_TcdSetModuloExt(*EDMA_Type* *base, *edma_tcd_t* *tcd, *edma_modulo_t* srcModulo, *edma_modulo_t* destModulo)

Sets the source modulo and the destination modulo for the eDMA TCD.

This function defines a specific address range specified to be the value after (SADDR + SOFF)/(DADDR + DOFF) calculation is performed or the original register value. It provides the ability to implement a circular data queue easily.

Parameters

- base – eDMA peripheral base address.
- tcd – A pointer to the TCD structure.
- srcModulo – A source modulo value.
- destModulo – A destination modulo value.

static inline void EDMA_TcdEnableAutoStopRequestExt(*EDMA_Type* *base, *edma_tcd_t* *tcd, bool enable)

Sets the auto stop request for the eDMA TCD.

If enabling the auto stop request, the eDMA hardware automatically disables the hardware channel request.

Parameters

- base – eDMA peripheral base address.
- tcd – A pointer to the TCD structure.
- enable – The command to enable (true) or disable (false).

void EDMA_TcdEnableInterruptsExt(*EDMA_Type* *base, *edma_tcd_t* *tcd, uint32_t mask)

Enables the interrupt source for the eDMA TCD.

Parameters

- base – eDMA peripheral base address.

- tcd – Point to the TCD structure.
- mask – The mask of interrupt source to be set. Users need to use the defined edma_interrupt_enable_t type.

void EDMA_TcdDisableInterruptsExt(*EDMA_Type* *base, *edma_tcd_t* *tcd, uint32_t mask)

Disables the interrupt source for the eDMA TCD.

Parameters

- base – eDMA peripheral base address.
- tcd – Point to the TCD structure.
- mask – The mask of interrupt source to be set. Users need to use the defined edma_interrupt_enable_t type.

void EDMA_TcdSetMajorOffsetConfigExt(*EDMA_Type* *base, *edma_tcd_t* *tcd, int32_t sourceOffset, int32_t destOffset)

Configures the eDMA TCD major offset feature.

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

Parameters

- base – eDMA peripheral base address.
- tcd – A point to the TCD structure.
- sourceOffset – source address offset wiil be applied to source address after major loop done.
- destOffset – destination address offset will be applied to source address after major loop done.

static inline void EDMA_EnableChannelRequest(*EDMA_Type* *base, uint32_t channel)

Enables the eDMA hardware channel request.

This function enables the hardware channel request.

Parameters

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

static inline void EDMA_DisableChannelRequest(*EDMA_Type* *base, uint32_t channel)

Disables the eDMA hardware channel request.

This function disables the hardware channel request.

Parameters

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

static inline void EDMA_TriggerChannelStart(*EDMA_Type* *base, uint32_t channel)

Starts the eDMA transfer by using the software trigger.

This function starts a minor loop transfer.

Parameters

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

uint32_t EDMA_GetRemainingMajorLoopCount(*EDMA_Type* *base, uint32_t channel)

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

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

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

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

Parameters

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

Returns

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

static inline uint32_t EDMA_GetErrorStatusFlags(*EDMA_Type* *base)

Gets the eDMA channel error status flags.

Parameters

- base – eDMA peripheral base address.

Returns

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

uint32_t EDMA_GetChannelStatusFlags(*EDMA_Type* *base, uint32_t channel)

Gets the eDMA channel status flags.

Parameters

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

Returns

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

void EDMA_ClearChannelStatusFlags(*EDMA_Type* *base, uint32_t channel, uint32_t mask)

Clears the eDMA channel status flags.

Parameters

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

status_t EDMA_CreateHandle(*edma_handle_t* *handle, *EDMA_Type* *base, uint32_t channel)

Creates the eDMA handle.

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

Parameters

- handle – eDMA handle pointer. The eDMA handle stores callback function and parameters.
- base – eDMA peripheral base address.
- channel – eDMA channel number.

Return values

- kStatus_Success –
- kStatus_InvalidArgument –

void EDMA_InstallTCDMemory(*edma_handle_t* *handle, *edma_tcd_t* *tcdPool, uint32_t tcdSize)

Installs the TCDs memory pool into the eDMA handle.

This function is called after the EDMA_CreateHandle to use scatter/gather feature. This function shall only be used while users need to use scatter gather mode. Scatter gather mode enables EDMA to load a new transfer control block (tcd) in hardware, and automatically reconfigure that DMA channel for a new transfer. Users need to prepare tcd memory and also configure tcds using interface EDMA_SubmitTransfer.

Parameters

- handle – eDMA handle pointer.
- tcdPool – A memory pool to store TCDs. It must be 32 bytes aligned.
- tcdSize – The number of TCD slots.

void EDMA_SetCallback(*edma_handle_t* *handle, *edma_callback* callback, void *userData)

Installs a callback function for the eDMA transfer.

This callback is called in the eDMA IRQ handler. Use the callback to do something after the current major loop transfer completes. This function will be called every time one tcd finished transfer.

Parameters

- handle – eDMA handle pointer.
- callback – eDMA callback function pointer.
- userData – A parameter for the callback function.

void EDMA_PrepareTransferConfig(*edma_transfer_config_t* *config, void *srcAddr, uint32_t srcWidth, int16_t srcOffset, void *destAddr, uint32_t destWidth, int16_t destOffset, uint32_t bytesEachRequest, uint32_t transferBytes)

Prepares the eDMA transfer structure configurations.

This function prepares the transfer configuration structure according to the user input.

Note: The data address and the data width must be consistent. For example, if the SRC is 4 bytes, the source address must be 4 bytes aligned, or it results in source address error (SAE). User can check if 128 bytes support is available for specific instance by FSL_FEATURE_EDMA_INSTANCE_SUPPORT_128_BYTES_TRANSFERn.

Parameters

- config – The user configuration structure of type edma_transfer_t.
- srcAddr – eDMA transfer source address.
- srcWidth – eDMA transfer source address width(bytes).
- srcOffset – source address offset.
- destAddr – eDMA transfer destination address.
- destWidth – eDMA transfer destination address width(bytes).
- destOffset – destination address offset.
- bytesEachRequest – eDMA transfer bytes per channel request.
- transferBytes – eDMA transfer bytes to be transferred.

void EDMA_PrepareTransfer(*edma_transfer_config_t* *config, void *srcAddr, uint32_t srcWidth, void *destAddr, uint32_t destWidth, uint32_t bytesEachRequest, uint32_t transferBytes, *edma_transfer_type_t* type)

Prepares the eDMA transfer structure.

This function prepares the transfer configuration structure according to the user input.

Note: The data address and the data width must be consistent. For example, if the SRC is 4 bytes, the source address must be 4 bytes aligned, or it results in source address error (SAE).

Parameters

- config – The user configuration structure of type edma_transfer_t.
- srcAddr – eDMA transfer source address.
- srcWidth – eDMA transfer source address width(bytes).
- destAddr – eDMA transfer destination address.
- destWidth – eDMA transfer destination address width(bytes).
- bytesEachRequest – eDMA transfer bytes per channel request.
- transferBytes – eDMA transfer bytes to be transferred.
- type – eDMA transfer type.

void EDMA_PrepareTransferTCD(*edma_handle_t* *handle, *edma_tcd_t* *tcd, void *srcAddr, uint32_t srcWidth, int16_t srcOffset, void *destAddr, uint32_t destWidth, int16_t destOffset, uint32_t bytesEachRequest, uint32_t transferBytes, *edma_tcd_t* *nextTcd)

Prepares the eDMA transfer content descriptor.

This function prepares the transfer content descriptor structure according to the user input.

Note: The data address and the data width must be consistent. For example, if the SRC is 4 bytes, the source address must be 4 bytes aligned, or it results in source address error (SAE).

Parameters

- handle – eDMA handle pointer.
- tcd – Pointer to eDMA transfer content descriptor structure.

- srcAddr – eDMA transfer source address.
- srcWidth – eDMA transfer source address width(bytes).
- srcOffset – source address offset.
- destAddr – eDMA transfer destination address.
- destWidth – eDMA transfer destination address width(bytes).
- destOffset – destination address offset.
- bytesEachRequest – eDMA transfer bytes per channel request.
- transferBytes – eDMA transfer bytes to be transferred.
- nextTcd – eDMA transfer linked TCD address.

status_t EDMA_SubmitTransferTCD(*edma_handle_t* *handle, *edma_tcd_t* *tcd)

Submits the eDMA transfer content descriptor.

This function submits the eDMA transfer request according to the transfer content descriptor. In scatter gather mode, call this function will add a configured tcd to the circular list of tcd pool. The tcd pools is setup by call function EDMA_InstallTCDMemory before.

Typical user case:

a. submit single transfer

```
edma_tcd_t tcd;
EDMA_PrepareTransferTCD(handle, tcd, ....)
EDMA_SubmitTransferTCD(handle, tcd)
EDMA_StartTransfer(handle)
```

b. submit static link transfer,

```
edma_tcd_t tcd[2];
EDMA_PrepareTransferTCD(handle, &tcd[0], ....)
EDMA_PrepareTransferTCD(handle, &tcd[1], ....)
EDMA_SubmitTransferTCD(handle, &tcd[0])
EDMA_StartTransfer(handle)
```

c. submit dynamic link transfer

```
edma_tcd_t tcdpool[2];
EDMA_InstallTCDMemory(&g_DMA_Handle, tcdpool, 2);
edma_tcd_t tcd;
EDMA_PrepareTransferTCD(handle, tcd, ....)
EDMA_SubmitTransferTCD(handle, tcd)
EDMA_PrepareTransferTCD(handle, tcd, ....)
EDMA_SubmitTransferTCD(handle, tcd)
EDMA_StartTransfer(handle)
```

d. submit loop transfer

```
edma_tcd_t tcd[2];
EDMA_PrepareTransferTCD(handle, &tcd[0], ...,&tcd[1])
EDMA_PrepareTransferTCD(handle, &tcd[1], ..., &tcd[0])
EDMA_SubmitTransferTCD(handle, &tcd[0])
EDMA_StartTransfer(handle)
```

Parameters

- handle – eDMA handle pointer.
- tcd – Pointer to eDMA transfer content descriptor structure.

Return values

- kStatus_EDMA_Success – It means submit transfer request succeed.
- kStatus_EDMA_QueueFull – It means TCD queue is full. Submit transfer request is not allowed.
- kStatus_EDMA_Busy – It means the given channel is busy, need to submit request later.

status_t EDMA_SubmitTransfer(*edma_handle_t* *handle, const *edma_transfer_config_t* *config)

Submits the eDMA transfer request.

This function submits the eDMA transfer request according to the transfer configuration structure. In scatter gather mode, call this function will add a configured tcd to the circular list of tcd pool. The tcd pools is setup by call function EDMA_InstallTCDMemory before.

Parameters

- handle – eDMA handle pointer.
- config – Pointer to eDMA transfer configuration structure.

Return values

- kStatus_EDMA_Success – It means submit transfer request succeed.
- kStatus_EDMA_QueueFull – It means TCD queue is full. Submit transfer request is not allowed.
- kStatus_EDMA_Busy – It means the given channel is busy, need to submit request later.

status_t EDMA_SubmitLoopTransfer(*edma_handle_t* *handle, *edma_transfer_config_t* *transfer, uint32_t transferLoopCount)

Submits the eDMA scatter gather transfer configurations.

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

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

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

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

---

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

---

Parameters

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

Return values

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

- kStatus_InvalidArgument – Invalid Argument

void EDMA_StartTransfer(*edma_handle_t* *handle)

eDMA starts transfer.

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

Parameters

- handle – eDMA handle pointer.

void EDMA_StopTransfer(*edma_handle_t* *handle)

eDMA stops transfer.

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

Parameters

- handle – eDMA handle pointer.

void EDMA_AbortTransfer(*edma_handle_t* *handle)

eDMA aborts transfer.

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

Parameters

- handle – DMA handle pointer.

static inline uint32_t EDMA_GetUnusedTCDNumber(*edma_handle_t* *handle)

Get unused TCD slot number.

This function gets current tcd index which is run. If the TCD pool pointer is NULL, it will return 0.

Parameters

- handle – DMA handle pointer.

Returns

The unused tcd slot number.

static inline uint32_t EDMA_GetNextTCDAddress(*edma_handle_t* *handle)

Get the next tcd address.

This function gets the next tcd address. If this is last TCD, return 0.

Parameters

- handle – DMA handle pointer.

Returns

The next TCD address.

void EDMA_HandleIRQ(*edma_handle_t* *handle)

eDMA IRQ handler for the current major loop transfer completion.

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

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

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

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

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

Parameters

- handle – eDMA handle pointer.

void EDMA_TcdInit(*EDMA_Type* *base, *edma_tcd_t* *tcdRegs)

Initialize all fields to 0 for the TCD structure.

This function initialize all fields for this TCD structure to 0.

Parameters

- base – eDMA peripheral base address.
- tcd – Pointer to the TCD structure.

FSL_EDMA_DRIVER_VERSION

eDMA driver version

Version 2.10.14.

_edma_transfer_status eDMA transfer status

Values:

enumerator kStatus_EDMA_QueueFull

TCD queue is full.

enumerator kStatus_EDMA_Busy

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

enum _edma_transfer_size

eDMA transfer configuration

Values:

enumerator kEDMA_TransferSize1Bytes

Source/Destination data transfer size is 1 byte every time

enumerator kEDMA_TransferSize2Bytes

Source/Destination data transfer size is 2 bytes every time

enumerator kEDMA_TransferSize4Bytes

Source/Destination data transfer size is 4 bytes every time

enumerator kEDMA_TransferSize8Bytes
Source/Destination data transfer size is 8 bytes every time

enumerator kEDMA_TransferSize16Bytes
Source/Destination data transfer size is 16 bytes every time

enumerator kEDMA_TransferSize32Bytes
Source/Destination data transfer size is 32 bytes every time

enumerator kEDMA_TransferSize64Bytes
Source/Destination data transfer size is 64 bytes every time

enumerator kEDMA_TransferSize128Bytes
Source/Destination data transfer size is 128 bytes every time

enum _edma_modulo
eDMA modulo configuration
Values:

enumerator kEDMA_ModuloDisable
Disable modulo

enumerator kEDMA_Modulo2bytes
Circular buffer size is 2 bytes.

enumerator kEDMA_Modulo4bytes
Circular buffer size is 4 bytes.

enumerator kEDMA_Modulo8bytes
Circular buffer size is 8 bytes.

enumerator kEDMA_Modulo16bytes
Circular buffer size is 16 bytes.

enumerator kEDMA_Modulo32bytes
Circular buffer size is 32 bytes.

enumerator kEDMA_Modulo64bytes
Circular buffer size is 64 bytes.

enumerator kEDMA_Modulo128bytes
Circular buffer size is 128 bytes.

enumerator kEDMA_Modulo256bytes
Circular buffer size is 256 bytes.

enumerator kEDMA_Modulo512bytes
Circular buffer size is 512 bytes.

enumerator kEDMA_Modulo1Kbytes
Circular buffer size is 1 K bytes.

enumerator kEDMA_Modulo2Kbytes
Circular buffer size is 2 K bytes.

enumerator kEDMA_Modulo4Kbytes
Circular buffer size is 4 K bytes.

enumerator kEDMA_Modulo8Kbytes
Circular buffer size is 8 K bytes.

enumerator kEDMA_Modulo16Kbytes
Circular buffer size is 16 K bytes.

enumerator kEDMA_Modulo32Kbytes
Circular buffer size is 32 K bytes.

enumerator kEDMA_Modulo64Kbytes
Circular buffer size is 64 K bytes.

enumerator kEDMA_Modulo128Kbytes
Circular buffer size is 128 K bytes.

enumerator kEDMA_Modulo256Kbytes
Circular buffer size is 256 K bytes.

enumerator kEDMA_Modulo512Kbytes
Circular buffer size is 512 K bytes.

enumerator kEDMA_Modulo1Mbytes
Circular buffer size is 1 M bytes.

enumerator kEDMA_Modulo2Mbytes
Circular buffer size is 2 M bytes.

enumerator kEDMA_Modulo4Mbytes
Circular buffer size is 4 M bytes.

enumerator kEDMA_Modulo8Mbytes
Circular buffer size is 8 M bytes.

enumerator kEDMA_Modulo16Mbytes
Circular buffer size is 16 M bytes.

enumerator kEDMA_Modulo32Mbytes
Circular buffer size is 32 M bytes.

enumerator kEDMA_Modulo64Mbytes
Circular buffer size is 64 M bytes.

enumerator kEDMA_Modulo128Mbytes
Circular buffer size is 128 M bytes.

enumerator kEDMA_Modulo256Mbytes
Circular buffer size is 256 M bytes.

enumerator kEDMA_Modulo512Mbytes
Circular buffer size is 512 M bytes.

enumerator kEDMA_Modulo1Gbytes
Circular buffer size is 1 G bytes.

enumerator kEDMA_Modulo2Gbytes
Circular buffer size is 2 G bytes.

enum _edma_bandwidth
Bandwidth control.
Values:

enumerator kEDMA_BandwidthStallNone
No eDMA engine stalls.

enumerator kEDMA_BandwidthStall4Cycle
eDMA engine stalls for 4 cycles after each read/write.

enumerator kEDMA_BandwidthStall8Cycle
eDMA engine stalls for 8 cycles after each read/write.

enum _edma_channel_link_type
Channel link type.
Values:

enumerator kEDMA_LinkNone
No channel link

enumerator kEDMA_MinorLink
Channel link after each minor loop

enumerator kEDMA_MajorLink
Channel link while major loop count exhausted

_edma_channel_status_flags eDMA channel status flags.
Values:

enumerator kEDMA_DoneFlag
DONE flag, set while transfer finished, CITER value exhausted

enumerator kEDMA_ErrorFlag
eDMA error flag, an error occurred in a transfer

enumerator kEDMA_InterruptFlag
eDMA interrupt flag, set while an interrupt occurred of this channel

_edma_error_status_flags eDMA channel error status flags.

Values:

enumerator kEDMA_DestinationBusErrorFlag
Bus error on destination address

enumerator kEDMA_SourceBusErrorFlag
Bus error on the source address

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

enumerator kEDMA_NbytesErrorFlag
NBYTES/CITER configuration error

enumerator kEDMA_DestinationOffsetErrorFlag
Destination offset not aligned with destination size

enumerator kEDMA_DestinationAddressErrorFlag
Destination address not aligned with destination size

enumerator kEDMA_SourceOffsetErrorFlag
Source offset not aligned with source size

enumerator kEDMA_SourceAddressErrorFlag
Source address not aligned with source size

enumerator kEDMA_ErrorChannelFlag
Error channel number of the cancelled channel number

enumerator kEDMA_TransferCanceledFlag
Transfer cancelled

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

_edma_interrupt_enable eDMA interrupt source

Values:

enumerator kEDMA_ErrorInterruptEnable
Enable interrupt while channel error occurs.

enumerator kEDMA_MajorInterruptEnable
Enable interrupt while major count exhausted.

enumerator kEDMA_HalfInterruptEnable
Enable interrupt while major count to half value.

enum _edma_transfer_type
eDMA transfer type
Values:

enumerator kEDMA_MemoryToMemory
Transfer from memory to memory

enumerator kEDMA_PeripheralToMemory
Transfer from peripheral to memory

enumerator kEDMA_MemoryToPeripheral
Transfer from memory to peripheral

enumerator kEDMA_PeripheralToPeripheral
Transfer from Peripheral to peripheral

enum edma_channel_memory_attribute
eDMA channel memory attribute
Values:

enumerator kEDMA_ChannelNoWriteNoReadNoCacheNoBuffer
No write allocate, no read allocate, non-cacheable, non-bufferable.

enumerator kEDMA_ChannelNoWriteNoReadNoCacheBufferable
No write allocate, no read allocate, non-cacheable, bufferable.

enumerator kEDMA_ChannelNoWriteNoReadCacheableNoBuffer
No write allocate, no read allocate, cacheable, non-bufferable.

enumerator kEDMA_ChannelNoWriteNoReadCacheableBufferable
No write allocate, no read allocate, cacheable, bufferable.

enumerator kEDMA_ChannelNoWriteReadNoCacheNoBuffer
No write allocate, read allocate, non-cacheable, non-bufferable.

enumerator kEDMA_ChannelNoWriteReadNoCacheBufferable
No write allocate, read allocate, non-cacheable, bufferable.

enumerator kEDMA_ChannelNoWriteReadCacheableNoBuffer
No write allocate, read allocate, cacheable, non-bufferable.

enumerator kEDMA_ChannelNoWriteReadCacheableBufferable
No write allocate, read allocate, cacheable, bufferable.

enumerator kEDMA_ChannelWriteNoReadNoCacheNoBuffer
write allocate, no read allocate, non-cacheable, non-bufferable.

enumerator kEDMA_ChannelWriteNoReadNoCacheBufferable
write allocate, no read allocate, non-cacheable, bufferable.

enumerator kEDMA_ChannelWriteNoReadCacheableNoBuffer
write allocate, no read allocate, cacheable, non-bufferable.

enumerator kEDMA_ChannelWriteNoReadCacheableBufferable
write allocate, no read allocate, cacheable, bufferable.

enumerator kEDMA_ChannelWriteReadNoCacheNoBuffer
write allocate, read allocate, non-cacheable, non-bufferable.

enumerator kEDMA_ChannelWriteReadNoCacheBufferable
write allocate, read allocate, non-cacheable, bufferable.

enumerator kEDMA_ChannelWriteReadCacheableNoBuffer
write allocate, read allocate, cacheable, non-bufferable.

enumerator kEDMA_ChannelWriteReadCacheableBufferable
write allocate, read allocate, cacheable, bufferable.

enum _edma_channel_swap_size
eDMA4 channel swap size
Values:

enumerator kEDMA_ChannelSwapDisabled
Swap is disabled.

enumerator kEDMA_ChannelReadWith8bitSwap
Swap occurs with respect to the read 8bit.

enumerator kEDMA_ChannelReadWith16bitSwap
Swap occurs with respect to the read 16bit.

enumerator kEDMA_ChannelReadWith32bitSwap
Swap occurs with respect to the read 32bit.

enumerator kEDMA_ChannelWriteWith8bitSwap
Swap occurs with respect to the write 8bit.

enumerator kEDMA_ChannelWriteWith16bitSwap
Swap occurs with respect to the write 16bit.

enumerator kEDMA_ChannelWriteWith32bitSwap
Swap occurs with respect to the write 32bit.

eDMA channel system bus information, _edma_channel_sys_bus_info

Values:

enumerator kEDMA_PrivilegedAccessLevel
Privileged Access Level for DMA transfers. 0b - User protection level; 1b - Privileged protection level.

enumerator kEDMA_MasterId
DMA's master ID when channel is active and master ID replication is enabled.

enum _edma_channel_access_type
eDMA4 channel access type

Values:

enumerator kEDMA_ChannelDataAccess
Data access for eDMA4 transfers.

enumerator kEDMA_ChannelInstructionAccess
Instruction access for eDMA4 transfers.

enum _edma_channel_protection_level
eDMA4 channel protection level

Values:

enumerator kEDMA_ChannelProtectionLevelUser
user protection level for eDMA transfers.

enumerator kEDMA_ChannelProtectionLevelPrivileged
Privileged protection level eDMA transfers.

typedef enum *_edma_transfer_size* edma_transfer_size_t
eDMA transfer configuration

typedef enum *_edma_modulo* edma_modulo_t
eDMA modulo configuration

typedef enum *_edma_bandwidth* edma_bandwidth_t
Bandwidth control.

typedef enum *_edma_channel_link_type* edma_channel_link_type_t
Channel link type.

typedef enum *_edma_transfer_type* edma_transfer_type_t

eDMA transfer type

typedef struct *_edma_channel_Preemption_config* edma_channel_Preemption_config_t

eDMA channel priority configuration

typedef struct *_edma_minor_offset_config* edma_minor_offset_config_t

eDMA minor offset configuration

typedef enum *edma_channel_memory_attribute* edma_channel_memory_attribute_t

eDMA channel memory attribute

typedef enum *_edma_channel_swap_size* edma_channel_swap_size_t

eDMA4 channel swap size

typedef enum *_edma_channel_access_type* edma_channel_access_type_t

eDMA4 channel access type

typedef enum *_edma_channel_protection_level* edma_channel_protection_level_t

eDMA4 channel protection level

typedef struct *_edma_channel_config* edma_channel_config_t

eDMA4 channel configuration

typedef *edma_core_tcd_t* edma_tcd_t

eDMA TCD.

This structure is same as TCD register which is described in reference manual, and is used to configure the scatter/gather feature as a next hardware TCD.

typedef struct *_edma_transfer_config* edma_transfer_config_t

eDMA channel transfer configuration

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

1.To perform a simple transfer, below members should be initialized at least .srcAddr - source address .dstAddr - destination address .srcWidthOfEachTransfer - data width of source address .dstWidthOfEachTransfer - data width of destination address, normally it should be as same as srcWidthOfEachTransfer .bytesEachRequest - bytes to be transferred in each DMA request .totalBytes - total bytes to be transferred .srcOffsetOfEachTransfer - offset value in bytes unit to be applied to source address as each source read is completed .dstOffsetOfEachTransfer - offset value in bytes unit to be applied to destination address as each destination write is completed enablchannelRequest - channel request can be enabled together with transfer configure submission

2.The transfer configuration structure also support advance feature: Programmable source/destination address range(MODULO) Programmable minor loop offset Programmable major loop offset Programmable channel chain feature Programmable channel transfer control descriptor link feature

---

Note: User should pay attention to the transfer size alignment limitation

a. the bytesEachRequest should align with the srcWidthOfEachTransfer and the dstWidthOfEachTransfer that is to say bytesEachRequest % srcWidthOfEachTransfer should be 0

b. the srcOffsetOfEachTransfer and dstOffsetOfEachTransfer must be aligne with transfer width

c. the totalBytes should align with the bytesEachRequest

d. the srcAddr should align with the srcWidthOfEachTransfer

e. the dstAddr should align with the dstWidthOfEachTransfer

f. the srcAddr should align with srcAddrModulo if modulo feature is enabled

g. the dstAddr should align with dstAddrModulo if modulo feature is enabled If anyone of above condition can not be satisfied, the eDMA interfaces will generate assert error.

---

typedef struct *_edma_config* edma_config_t

eDMA global configuration structure.

typedef void (*edma_callback)(struct *_edma_handle* *handle, void *userData, bool transferDone, uint32_t tcds)

Define callback function for eDMA.

This callback function is called in the EDMA interrupt handle. In normal mode, run into callback function means the transfer users need is done. In scatter gather mode, run into callback function means a transfer control block (tcd) is finished. Not all transfer finished, users can get the finished tcd numbers using interface EDMA_GetUnusedTCDNumber.

Param handle
EDMA handle pointer, users shall not touch the values inside.

Param userData
The callback user parameter pointer. Users can use this parameter to involve things users need to change in EDMA callback function.

Param transferDone
If the current loaded transfer done. In normal mode it means if all transfer done. In scatter gather mode, this parameter shows is the current transfer block in EDMA register is done. As the load of core is different, it will be different if the new tcd loaded into EDMA registers while this callback called. If true, it always means new tcd still not loaded into registers, while false means new tcd already loaded into registers.

Param tcds
How many tcds are done from the last callback. This parameter only used in scatter gather mode. It tells user how many tcds are finished between the last callback and this.

typedef struct *_edma_handle* edma_handle_t

eDMA transfer handle structure

FSL_EDMA_DRIVER_UNIFIED

eDMA driver name.

This is the unified eDMA driver serving the eDMA3, eDMA4 and eDMA5 IP versions. Its Kconfig component is driver.edma_unified; the historical driver.edma4 component and the FSL_EDMA_DRIVER_EDMA4 macro are retained as deprecated aliases for backward compatibility. The version-specific edma4_* / edma5_* identifiers inside this driver refer to the corresponding IP TCD layout, not to the component name.

FSL_EDMA_DRIVER_EDMA4
Deprecated alias of FSL_EDMA_DRIVER_UNIFIED; use FSL_EDMA_DRIVER_UNIFIED.

EDMA_ALLOCATE_TCD(name, number)
Macro used for allocate edma TCD.

DMA_DCHPRI_INDEX(channel)
Compute the offset unit from DCHPRI3.

struct _edma_channel_Preemption_config
#include <fsl_edma.h> eDMA channel priority configuration

Public Members

bool enableChannelPreemption
If true: a channel can be suspended by other channel with higher priority

bool enablePreemptAbility
If true: a channel can suspend other channel with low priority

uint8_t channelPriority
Channel priority

struct _edma_minor_offset_config
#include <fsl_edma.h> eDMA minor offset configuration

Public Members

bool enableSrcMinorOffset
Enable(true) or Disable(false) source minor loop offset.

bool enableDestMinorOffset
Enable(true) or Disable(false) destination minor loop offset.

uint32_t minorOffset
Offset for a minor loop mapping.

struct _edma_channel_config
#include <fsl_edma.h> eDMA4 channel configuration

Public Members

edma_channel_Preemption_config_t channelPreemptionConfig
channel preemption configuration

edma_channel_memory_attribute_t channelReadMemoryAttribute
channel memory read attribute configuration

edma_channel_memory_attribute_t channelWriteMemoryAttribute
channel memory write attribute configuration

edma_channel_swap_size_t channelSwapSize
channel swap size configuration

edma_channel_access_type_t channelAccessType
channel access type configuration

uint8_t channelDataSignExtensionBitPosition
channel data sign extension bit psition configuration

uint32_t channelRequestSource
hardware service request source for the channel

bool enableMasterIDReplication
enable master ID replication

edma_channel_protection_level_t protectionLevel
protection level

struct __edma__transfer__config
#include <fsl_edma.h> eDMA channel transfer configuration

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

1.To perform a simple transfer, below members should be initialized at least .srcAddr - source address .dstAddr - destination address .srcWidthOfEachTransfer - data width of source address .dstWidthOfEachTransfer - data width of destination address, normally it should be as same as srcWidthOfEachTransfer .bytesEachRequest - bytes to be transferred in each DMA request .totalBytes - total bytes to be transferred .srcOffsetOfEachTransfer - offset value in bytes unit to be applied to source address as each source read is completed .dstOffsetOfEachTransfer - offset value in bytes unit to be applied to destination address as each destination write is completed enablchannelRequest - channel request can be enabled together with transfer configure submission

2.The transfer configuration structure also support advance feature: Programmable source/destination address range(MODULO) Programmable minor loop offset Programmable major loop offset Programmable channel chain feature Programmable channel transfer control descriptor link feature

---

Note: User should pay attention to the transfer size alignment limitation

a. the bytesEachRequest should align with the srcWidthOfEachTransfer and the dstWidthOfEachTransfer that is to say bytesEachRequest % srcWidthOfEachTransfer should be 0

b. the srcOffsetOfEachTransfer and dstOffsetOfEachTransfer must be aligne with transfer width

c. the totalBytes should align with the bytesEachRequest

d. the srcAddr should align with the srcWidthOfEachTransfer

e. the dstAddr should align with the dstWidthOfEachTransfer

f. the srcAddr should align with srcAddrModulo if modulo feature is enabled

g. the dstAddr should align with dstAddrModulo if modulo feature is enabled If anyone of above condition can not be satisfied, the eDMA interfaces will generate assert error.

Public Members

uint32_t srcAddr

Source data address.

uint32_t destAddr

Destination data address.

edma_transfer_size_t srcTransferSize

Source data transfer size.

edma_transfer_size_t destTransferSize

Destination data transfer size.

int16_t srcOffset

Sign-extended offset value in byte unit applied to the current source address to form the next-state value as each source read is completed

int16_t destOffset

Sign-extended offset value in byte unit applied to the current destination address to form the next-state value as each destination write is completed.

uint32_t minorLoopBytes

bytes in each minor loop or each request range: 1 - (2^30 -1) when minor loop mapping is enabled range: 1 - (2^10 - 1) when minor loop mapping is enabled and source or dest minor loop offset is enabled range: 1 - (2^32 - 1) when minor loop mapping is disabled

uint32_t majorLoopCounts

minor loop counts in each major loop, should be 1 at least for each transfer range: (0 - (2^15 - 1)) when minor loop channel link is disabled range: (0 - (2^9 - 1)) when minor loop channel link is enabled total bytes in a transfer = minorLoopCountsEachMajor-Loop * bytesEachMinorLoop

uint16_t enabledInterruptMask

channel interrupt to enable, can be OR'ed value of _edma_interrupt_enable

edma_modulo_t srcAddrModulo

source circular data queue range

int32_t srcMajorLoopOffset

source major loop offset

edma_modulo_t dstAddrModulo

destination circular data queue range

int32_t dstMajorLoopOffset
: destination major loop offset

bool enableSrcMinorLoopOffset
: enable source minor loop offset

bool enableDstMinorLoopOffset
: enable dest minor loop offset

int32_t minorLoopOffset
: burst offset, the offset will be applied after minor loop update

bool enableChannelMajorLoopLink
: channel link when major loop complete

uint32_t majorLoopLinkChannel
: major loop link channel number

bool enableChannelMinorLoopLink
: channel link when minor loop complete

uint32_t minorLoopLinkChannel
: minor loop link channel number

edma_tcd_t *linkTCD
: pointer to the link transfer control descriptor

struct __edma_config
: *#include <fsl_edma.h>* eDMA global configuration structure.

Public Members

bool enableMasterIdReplication
: Enable (true) master ID replication. If Master ID replication is disabled, the privileged protection level (supervisor mode) for eDMA4 transfers is used.

bool enableGlobalChannelLink
: Enable(true) channel linking is available and controlled by each channel's link settings.

bool enableHaltOnError
: Enable (true) transfer halt on error. Any error causes the HALT bit to set. Subsequently, all service requests are ignored until the HALT bit is cleared.

bool enableDebugMode
: Enable(true) eDMA4 debug mode. When in debug mode, the eDMA4 stalls the start of a new channel. Executing channels are allowed to complete.

bool enableRoundRobinArbitration

Enable(true) channel linking is available and controlled by each channel's link settings.

edma_channel_config_t *channelConfig[1]

channel preemption configuration

struct __edma_handle

#include <fsl_edma.h> eDMA transfer handle structure

Public Members

edma_callback callback

Callback function for major count exhausted.

void *userData

Callback function parameter.

EDMA_ChannelType *channelBase

eDMA peripheral channel base address.

EDMA_Type *base

eDMA peripheral base address

EDMA_TCDType *tcdBase

eDMA peripheral tcd base address.

edma_tcd_t *tcdPool

Pointer to memory stored TCDs.

uint32_t channel

eDMA channel number.

volatile int8_t header

The first TCD index. Should point to the next TCD to be loaded into the eDMA engine.

volatile int8_t tail

The last TCD index. Should point to the next TCD to be stored into the memory pool.

volatile int8_t tcdUsed

The number of used TCD slots. Should reflect the number of TCDs can be used/loaded in the memory.

volatile int8_t tcdSize

The total number of TCD slots in the queue.

2.8 eDMA core Driver

enum _edma_tcd_type

eDMA tcd flag type

Values:

enumerator kEDMA_EDMA4Flag

Data access for eDMA4 transfers.

enumerator kEDMA_EDMA5Flag

Instruction access for eDMA4 transfers.

typedef struct *_edma_core_mp* edma_core_mp_t

edma core channel struture definition

typedef struct *_edma_core_channel* edma_core_channel_t

edma core channel struture definition

typedef enum *_edma_tcd_type* edma_tcd_type_t

eDMA tcd flag type

typedef struct *_edma5_core_tcd* edma5_core_tcd_t

edma5 core TCD struture definition

typedef struct *_edma4_core_tcd* edma4_core_tcd_t

edma4 core TCD struture definition

typedef struct *_edma_core_tcd* edma_core_tcd_t

edma core TCD struture definition

typedef *edma_core_channel_t* EDMA_ChannelType

EDMA typedef.

typedef *edma_core_tcd_t* EDMA_TCDType

typedef void EDMA_Type

DMA_CORE_MP_CSR_EDBG_MASK

DMA_CORE_MP_CSR_ERCA_MASK

DMA_CORE_MP_CSR_HAE_MASK

DMA_CORE_MP_CSR_HALT_MASK

DMA_CORE_MP_CSR_GCLC_MASK

DMA_CORE_MP_CSR_GMRC_MASK

DMA_CORE_MP_CSR_EDBG(**x**)

DMA_CORE_MP_CSR_ERCA(**x**)

DMA_CORE_MP_CSR_HAE(**x**)

DMA_CORE_MP_CSR_HALT(**x**)

DMA_CORE_MP_CSR_GCLC(**x**)

DMA_CORE_MP_CSR_GMRC(**x**)

DMA_CSR_INTMAJOR_MASK

DMA_CSR_INTHALF_MASK

DMA_CSR_DREQ_MASK

DMA_CSR_ESG_MASK

DMA_CSR_BWC_MASK

DMA_CSR_BWC(**x**)

DMA_CSR_START_MASK

DMA_CITER_ELINKNO_CITER_MASK

DMA_BITER_ELINKNO_BITER_MASK

DMA_CITER_ELINKNO_CITER_SHIFT

DMA_CITER_ELINKYES_CITER_MASK

DMA_CITER_ELINKYES_CITER_SHIFT

DMA_ATTR_SMOD_MASK

DMA_ATTR_DMOD_MASK

DMA_ATTR_SSIZE_MASK

DMA_ATTR_SSIZE_SHIFT

DMA_ATTR_DSIZE_MASK

DMA_ATTR_DSIZE_SHIFT

DMA_CITER_ELINKNO_ELINK_MASK

DMA_CSR_MAJORELINK_MASK

DMA_BITER_ELINKYES_ELINK_MASK

DMA_CITER_ELINKYES_ELINK_MASK

DMA_CSR_MAJORLINKCH_MASK

DMA_BITER_ELINKYES_LINKCH_MASK

DMA_CITER_ELINKYES_LINKCH_MASK

DMA_NBYTES_MLOFFYES_MLOFF_MASK

DMA_NBYTES_MLOFFYES_DMLOE_MASK

DMA_NBYTES_MLOFFYES_SMLOE_MASK

DMA_NBYTES_MLOFFNO_NBYTES_MASK

DMA_ATTR_DMOD(x)

DMA_ATTR_SMOD(x)

DMA_BITER_ELINKYES_LINKCH(x)

DMA_CITER_ELINKYES_LINKCH(x)

DMA_NBYTES_MLOFFYES_MLOFF(x)

DMA_NBYTES_MLOFFYES_DMLOE(x)

DMA_NBYTES_MLOFFYES_SMLOE(x)

DMA_NBYTES_MLOFFNO_NBYTES(x)

DMA_NBYTES_MLOFFYES_NBYTES(x)

DMA_ATTR_DSIZE(x)

DMA_ATTR_SSIZE(x)

DMA_CSR_DREQ(x)

DMA_CSR_MAJORLINKCH(x)

DMA_CH_MATTR_WCACHE(x)

DMA_CH_MATTR_RCACHE(x)

DMA_CH_CSR_SIGNEXT_MASK

DMA_CH_CSR_SIGNEXT_SHIFT

DMA_CH_CSR_SWAP_MASK

DMA_CH_CSR_SWAP_SHIFT

DMA_CH_SBR_INSTR_MASK

DMA_CH_SBR_INSTR_SHIFT

DMA_CH_SBR_EMI_MASK

DMA_CH_SBR_EMI_SHIFT

DMA_CH_MUX_SOURCE(x)

DMA_ERR_DBE_FLAG
: DMA error flag.

DMA_ERR_SBE_FLAG

DMA_ERR_SGE_FLAG

DMA_ERR_NCE_FLAG

DMA_ERR_DOE_FLAG

DMA_ERR_DAE_FLAG

DMA_ERR_SOE_FLAG

DMA_ERR_SAE_FLAG

DMA_ERR_ERRCHAN_FLAG

DMA_ERR_ECX_FLAG

DMA_ERR_FLAG

DMA_CLEAR_DONE_STATUS(base, channel)
: get/clear DONE bit

DMA_GET_DONE_STATUS(base, channel)

DMA_ENABLE_ERROR_INT(base, channel)
: enable/disable error interupt

DMA_DISABLE_ERROR_INT(base, channel)

DMA__CLEAR__ERROR__STATUS(base, channel)
get/clear error status

DMA__GET__ERROR__STATUS(base, channel)

DMA__CLEAR__INT__STATUS(base, channel)
get/clear INT status

DMA__GET__INT__STATUS(base, channel)

DMA__ENABLE__MAJOR__INT(base, channel)
enable/dsiable MAJOR/HALF INT

DMA__ENABLE__HALF__INT(base, channel)

DMA__DISABLE__MAJOR__INT(base, channel)

DMA__DISABLE__HALF__INT(base, channel)

EDMA__TCD__ALIGN__SIZE
EDMA tcd align size.

EDMA__CORE__BASE(base)
EDMA base address convert macro.

EDMA__MP__BASE(base)

EDMA__CHANNEL__BASE(base, channel)

EDMA__TCD__BASE(base, channel)

EDMA__TCD__TYPE(x)
EDMA TCD type macro.

EDMA__TCD__SADDR(tcd, flag)
EDMA TCD address convert macro.

EDMA__TCD__SOFF(tcd, flag)

EDMA__TCD__ATTR(tcd, flag)

EDMA__TCD__NBYTES(tcd, flag)

EDMA__TCD__SLAST(tcd, flag)

EDMA__TCD__DADDR(tcd, flag)

EDMA__TCD__DOFF(tcd, flag)

EDMA__TCD__CITER(tcd, flag)

EDMA__TCD__DLAST__SGA(tcd, flag)

EDMA__TCD__CSR(tcd, flag)

EDMA__TCD__BITER(tcd, flag)

struct __edma__core__mp
#include <fsl_edma_core.h> edma core channel struture definition

Public Members

___IO uint32_t MP_CSR
Channel Control and Status, array offset: 0x10000, array step: 0x10000

___IO uint32_t MP_ES
Channel Error Status, array offset: 0x10004, array step: 0x10000

struct _edma_core_channel
#include <fsl_edma_core.h> edma core channel struture definition

Public Members

___IO uint32_t CH_CSR
Channel Control and Status, array offset: 0x10000, array step: 0x10000

___IO uint32_t CH_ES
Channel Error Status, array offset: 0x10004, array step: 0x10000

___IO uint32_t CH_INT
Channel Interrupt Status, array offset: 0x10008, array step: 0x10000

___IO uint32_t CH_SBR
Channel System Bus, array offset: 0x1000C, array step: 0x10000

___IO uint32_t CH_PRI
Channel Priority, array offset: 0x10010, array step: 0x10000

struct _edma5_core_tcd
#include <fsl_edma_core.h> edma5 core TCD struture definition

Public Members

___IO uint32_t SADDR
SADDR register, used to save source address

___IO uint32_t SADDR_HIGH
SADDR HIGH register, used to save source address

___IO uint16_t SOFF
SOFF register, save offset bytes every transfer

___IO uint16_t ATTR
ATTR register, source/destination transfer size and modulo

___IO uint32_t NBYTES
Nbytes register, minor loop length in bytes

___IO uint32_t SLAST
SLAST register

___IO uint32_t SLAST_SDA_HIGH
SLAST SDA HIGH register

___IO uint32_t DADDR
DADDR register, used for destination address

___IO uint32_t DADDR_HIGH
DADDR HIGH register, used for destination address

___IO uint32_t DLAST_SGA
DLASTSGA register, next tcd address used in scatter-gather mode

___IO uint32_t DLAST_SGA_HIGH
DLASTSGA HIGH register, next tcd address used in scatter-gather mode

___IO uint16_t DOFF
DOFF register, used for destination offset

___IO uint16_t CITER
CITER register, current minor loop numbers, for unfinished minor loop.

___IO uint16_t CSR
CSR register, for TCD control status

___IO uint16_t BITER
BITER register, begin minor loop count.

uint8_t RESERVED[16]
Aligned 64 bytes

struct _edma4_core_tcd
#include <fsl_edma_core.h> edma4 core TCD struture definition

Public Members

___IO uint32_t SADDR
SADDR register, used to save source address

___IO uint16_t SOFF
SOFF register, save offset bytes every transfer

___IO uint16_t ATTR
ATTR register, source/destination transfer size and modulo

___IO uint32_t NBYTES
Nbytes register, minor loop length in bytes

___IO uint32_t SLAST
SLAST register

___IO uint32_t DADDR
DADDR register, used for destination address

___IO uint16_t DOFF
DOFF register, used for destination offset

___IO uint16_t CITER
CITER register, current minor loop numbers, for unfinished minor loop.

___IO uint32_t DLAST_SGA
DLASTSGA register, next tcd address used in scatter-gather mode

___IO uint16_t CSR
CSR register, for TCD control status

___IO uint16_t BITER
BITER register, begin minor loop count.

struct _edma_core_tcd
#include <fsl_edma_core.h> edma core TCD struture definition

union MP_REGS

Public Members

struct *_edma_core_mp* EDMA5_REG

struct EDMA5_REG

Public Members

___IO uint32_t MP_INT_LOW
Channel Control and Status, array offset: 0x10008, array step: 0x10000

___I uint32_t MP_INT_HIGH
Channel Control and Status, array offset: 0x1000C, array step: 0x10000

___I uint32_t MP_HRS_LOW
Channel Control and Status, array offset: 0x10010, array step: 0x10000

___I uint32_t MP_HRS_HIGH
Channel Control and Status, array offset: 0x10014, array step: 0x10000

___IO uint32_t MP_STOPCH
Channel Control and Status, array offset: 0x10020, array step: 0x10000

___I uint32_t MP_SSR_LOW
Channel Control and Status, array offset: 0x10030, array step: 0x10000

___I uint32_t MP_SSR_HIGH
Channel Control and Status, array offset: 0x10034, array step: 0x10000

___IO uint32_t CH_GRPRI [64]
Channel Control and Status, array offset: 0x10100, array step: 0x10000

___IO uint32_t CH_MUX [64]
Channel Control and Status, array offset: 0x10200, array step: 0x10000

___IO uint32_t CH_PROT [64]
Channel Control and Status, array offset: 0x10400, array step: 0x10000

union CH_REGS

Public Members

struct *_edma_core_channel* EDMA5_REG

struct *_edma_core_channel* EDMA4_REG

struct EDMA5_REG

Public Members

___IO uint32_t CH_MATTR
Memory Attributes Register, array offset: 0x10018, array step: 0x8000

struct EDMA4_REG

Public Members

___IO uint32_t CH_MUX
Channel Multiplexor Configuration, array offset: 0x10014, array step: 0x10000

___IO uint16_t CH_MATTR
Memory Attributes Register, array offset: 0x10018, array step: 0x8000

union TCD_REGS

Public Members

edma4_core_tcd_t edma4_tcd

2.9 eDMA soc Driver

2.10 EIM: error injection module

FSL_EIM_DRIVER_VERSION
Driver version.

void EIM_Init(EIM_Type *base)
EIM module initialization function.

Parameters

- base – EIM base address.

void EIM_Deinit(EIM_Type *base)
De-initializes the EIM.

2.11 EQDC: Enhanced Quadrature Encoder/Decoder

void EQDC_Init(EQDC_Type *base, const *eqdc_config_t* *psConfig)
Initializes the EQDC module.

This function initializes the EQDC by enabling the IP bus clock (optional).

Parameters

- base – EQDC peripheral base address.
- psConfig – Pointer to configuration structure.

void EQDC_GetDefaultConfig(*eqdc_config_t* *psConfig)
Gets an available pre-defined configuration.

The default value are:

```
psConfig->enableReverseDirection          = false;
psConfig->countOnce                       = false;
psConfig->operateMode                     = kEQDC_QuadratureDecodeOperationMode;
psConfig->countMode                       = kEQDC_QuadratureX4;
psConfig->homeEnableInitPosCounterMode    = kEQDC_HomeInitPosCounterDisabled;
psConfig->indexPresetInitPosCounterMode   = kEQDC_IndexInitPosCounterDisabled;
psConfig->enableIndexInitPositionCounter  = false;
psConfig->enableDma                       = false;
psConfig->bufferedRegisterLoadMode        = false;
psConfig->enableTriggerInitPositionCounter  = false;
psConfig->enableTriggerClearPositionRegisters = false;
psConfig->enableTriggerHoldPositionRegisters  = false;
psConfig->enableWatchdog                  = false;
psConfig->watchdogTimeoutValue            = 0xFFFFU;
psConfig->filterPhaseA                    = 0U;
psConfig->filterPhaseB                    = 0U;
psConfig->filterIndPre                    = 0U;
```

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```
psConfig->filterHomEna                  = 0U;
psConfig->filterClockSourceselection    = false;
psConfig->filterSampleCount             = kEQDC_Filter3Samples;
psConfig->filterSamplePeriod            = 0U;
psConfig->outputPulseMode               = kEQDC_OutputPulseOnCounterEqualCompare;
psConfig->positionCompareValue[0]       = 0xFFFFFFFFU;
psConfig->positionCompareValue[1]       = 0xFFFFFFFFU;
psConfig->positionCompareValue[2]       = 0xFFFFFFFFU;
psConfig->positionCompareValue[3]       = 0xFFFFFFFFU;
psConfig->revolutionCountCondition      = kEQDC_RevolutionCountOnIndexPulse;
psConfig->positionModulusValue          = 0U;
psConfig->positionInitialValue          = 0U;
psConfig->positionCounterValue          = 0U;
psConfig->enablePeriodMeasurement       = false;
psConfig->prescaler                     = kEQDC_Prescaler1;
psConfig->enabledInterruptsMask         = 0U;
```

Parameters

- psConfig – Pointer to configuration structure.

void EQDC_Deinit(EQDC_Type *base)

De-initializes the EQDC module.

This function deinitializes the EQDC by disabling the IP bus clock (optional).

Parameters

- base – EQDC peripheral base address.

void EQDC_SetOperateMode(EQDC_Type *base, *eqdc_operate_mode_t* operateMode)

Initializes the mode of operation.

This function initializes mode of operation by enabling the IP bus clock (optional).

Parameters

- base – EQDC peripheral base address.
- operateMode – Select operation mode.

static inline void EQDC_SetCountMode(EQDC_Type *base, *eqdc_count_mode_t* countMode)

Initializes the mode of count.

These bits control the basic counting and behavior of Position Counter and Position Difference Counter. Setting CTRL[REV] to 1 can reverse the counting direction. 1.In quadrature Mode (CTRL[PH1] = 0): 00b - CM0: Normal/Reverse Quadrature X4 01b - CM1: Normal/Reverse Quadrature X2 10b - CM2: Normal/Reverse Quadrature X1 11b - CM3: Reserved 2.In Single Phase Mode (CTRL[PH1] = 1): 00b - CM0: UP/DOWN Pulse Count Mode 01b - CM1: Signed Mode, count PHASEA rising/falling edge, position counter counts up when PHASEB is low and counts down when PHASEB is high 10b - CM2: Signed Count Mode,count PHASEA rising edge only, position counter counts up when PHASEB is low and counts down when PHASEB is high 11b - CM3: Reserved

Parameters

- base – EQDC peripheral base address.
- countMode – Select count mode.

static inline void EQDC_EnableWatchdog(EQDC_Type *base, bool bEnable)

Enable watchdog for EQDC module.

Parameters

- base – EQDC peripheral base address
- bEnable – Enables or disables the watchdog

static inline void EQDC_SetWatchdogTimeout(EQDC_Type *base, uint16_t u16Timeout)

Set watchdog timeout value.

Parameters

- base – EQDC peripheral base address
- u16Timeout – Number of clock cycles, plus one clock cycle that the watchdog timer counts before timing out

static inline void EQDC_EnableDMA(EQDC_Type *base, bool bEnable)

Enable DMA for EQDC module.

Parameters

- base – EQDC peripheral base address
- bEnable – Enables or disables the DMA

static inline void EQDC_SetBufferedRegisterLoadUpdateMode(EQDC_Type *base)

Set Buffered Register Load (Update) Mode.

This bit selects the loading time point of the buffered compare registers UCOMPx/LCOMPx, x=0~3, initial register (UINIT/LINIT), and modulus register (UMOD/LMOD). Buffered registers are loaded and take effect at the next roll-over or roll-under if CTRL[LDOK] is set.

Parameters

- base – EQDC peripheral base address

static inline void EQDC_ClearBufferedRegisterLoadUpdateMode(EQDC_Type *base)

Clear Buffered Register Load (Update) Mode.

Buffered Register Load (Update) Mode bit selects the loading time point of the buffered compare registers UCOMPx/LCOMPx, x=0~3, initial register (UINIT/LINIT), and modulus register (UMOD/LMOD). Buffered registers are loaded and take effect immediately upon CTRL[LDOK] is set.

Parameters

- base – EQDC peripheral base address

static inline void EQDC_SetEqdcLdok(EQDC_Type *base)

Set load okay.

Load okay enables that the outer-set values of buffered compare registers (UCOMPx/LCOMPx, x=0~3), initial register(UINIT/LINIT) and modulus register(UMOD/LMOD) can be loaded into their inner-sets and take effect. When LDOK is set, this loading action occurs at the next position counter roll-over or roll-under if CTRL2[LDMOD] is set, or it occurs immediately if CTRL2[LDMOD] is cleared. LDOK is automatically cleared after the values in outer-set is loaded into the inner-set.

Parameters

- base – EQDC peripheral base address.

static inline uint16_t EQDC_GetEqdcLdok(EQDC_Type *base)

Get load okay.

Parameters

- base – EQDC peripheral base address.

static inline void EQDC_ClearEqdcLdok(EQDC_Type *base)

Clear load okay.

Parameters

- base – EQDC peripheral base address.

static inline uint32_t EQDC_GetStatusFlags(EQDC_Type *base)

Get the status flags.

Parameters

- base – EQDC peripheral base address.

Returns

Logical OR'ed value of the status flags, *_eqdc_status_flags*.

static inline void EQDC_ClearStatusFlags(EQDC_Type *base, uint32_t u32Flags)

Clear the status flags.

Parameters

- base – EQDC peripheral base address.
- u32Flags – Logical OR'ed value of the flags to clear, *_eqdc_status_flags*.

static inline uint16_t EQDC_GetSignalStatusFlags(EQDC_Type *base)

Get the signals' real-time status.

Parameters

- base – EQDC peripheral base address.

Returns

Logical OR'ed value of the real-time signal status, *_eqdc_signal_status*.

static inline *eqdc_count_direction_flag_t* EQDC_GetLastCountDirection(EQDC_Type *base)

Get the direction of the last count.

Parameters

- base – EQDC peripheral base address.

Returns

Direction of the last count.

static inline void EQDC_EnableInterrupts(EQDC_Type *base, uint32_t u32Interrupts)

Enable the interrupts.

Parameters

- base – EQDC peripheral base address.
- u32Interrupts – Logical OR'ed value of the interrupts, *_eqdc_interrupt_enable*.

static inline void EQDC_DisableInterrupts(EQDC_Type *base, uint32_t u32Interrupts)

Disable the interrupts.

Parameters

- base – EQDC peripheral base address.
- u32Interrupts – Logical OR'ed value of the interrupts, *_eqdc_interrupt_enable*.

static inline void EQDC_DoSoftwareLoadInitialPositionValue(EQDC_Type *base)

Load the initial position value to position counter.

Software trigger to load the initial position value (UINIT and LINIT) contents to position counter (UPOS and LPOS), so that to provide the consistent operation the position counter registers.

Parameters

- base – EQDC peripheral base address.

static inline void EQDC_SetInitialPositionValue(EQDC_Type *base, uint32_t u32PositionInitValue)

Set initial position value for EQDC module.

Set the position counter initial value (UINIT, LINIT). After writing values to the UINIT and LINIT registers, the values are "buffered" into outer-set registers temporarily. Values will be loaded into inner-set registers and take effect using the following two methods:

a. If CTRL2[LDMODE] is 1, "buffered" values are loaded into inner-set and take effect at the next roll-over or roll-under if CTRL[LDOK] is set.

b. If CTRL2[LDMODE] is 0, "buffered" values are loaded into inner-set and take effect immediately when CTRL[LDOK] is set.

Parameters

- base – EQDC peripheral base address
- u32PositionInitValue – Position initial value

static inline void EQDC_SetPositionCounterValue(EQDC_Type *base, uint32_t positionCounterValue)

Set position counter value.

Set the position counter value (POS or UPOS, LPOS).

Parameters

- base – EQDC peripheral base address
- positionCounterValue – Position counter value

static inline void EQDC_SetPositionModulusValue(EQDC_Type *base, uint32_t positionModulusValue)

Set position counter modulus value.

Set the position counter modulus value (UMOD, LMOD). After writing values to the UMOD and LMOD registers, the values are "buffered" into outer-set registers temporarily. Values will be loaded into inner-set registers and take effect using the following two methods:

a. If CTRL2[LDMODE] is 1, "buffered" values are loaded into inner-set and take effect at the next roll-over or roll-under if CTRL[LDOK] is set.

b. If CTRL2[LDMODE] is 0, "buffered" values are loaded into inner-set and take effect immediately when CTRL[LDOK] is set.

Parameters

- base – EQDC peripheral base address
- positionModulusValue – Position modulus value

static inline void EQDC_SetPositionCompare0Value(EQDC_Type *base, uint32_t u32PositionComp0Value)

Set position counter compare 0 value.

Set the position counter compare 0 value (UCOMP0, LCOMP0). After writing values to the UCOMP0 and LCOMP0 registers, the values are "buffered" into outer-set registers temporarily. Values will be loaded into inner-set registers and take effect using the following two methods:

a. If CTRL2[LDMODE] is 1, "buffered" values are loaded into inner-set and take effect at the next roll-over or roll-under if CTRL[LDOK] is set.

b. If CTRL2[LDMODE] is 0, "buffered" values are loaded into inner-set and take effect immediately when CTRL[LDOK] is set.

Parameters

- base – EQDC peripheral base address
- u32PositionComp0Value – Position modulus value

static inline void EQDC_SetPositionCompare1Value(EQDC_Type *base, uint32_t u32PositionComp1Value)

Set position counter compare 1 value.

Set the position counter compare 1 value (UCOMP1, LCOMP1). After writing values to the UCOMP1 and LCOMP1 registers, the values are "buffered" into outer-set registers temporarily. Values will be loaded into inner-set registers and take effect using the following two methods:

a. If CTRL2[LDMODE] is 1, "buffered" values are loaded into inner-set and take effect at the next roll-over or roll-under if CTRL[LDOK] is set.

b. If CTRL2[LDMODE] is 0, "buffered" values are loaded into inner-set and take effect immediately when CTRL[LDOK] is set.

Parameters

- base – EQDC peripheral base address
- u32PositionComp1Value – Position modulus value

static inline void EQDC_SetPositionCompare2Value(EQDC_Type *base, uint32_t u32PositionComp2Value)

Set position counter compare 2 value.

Set the position counter compare 2 value (UCOMP2, LCOMP2). After writing values to the UCOMP2 and LCOMP2 registers, the values are "buffered" into outer-set registers temporarily. Values will be loaded into inner-set registers and take effect using the following two methods:

a. If CTRL2[LDMODE] is 1, "buffered" values are loaded into inner-set and take effect at the next roll-over or roll-under if CTRL[LDOK] is set.

b. If CTRL2[LDMODE] is 0, "buffered" values are loaded into inner-set and take effect immediately when CTRL[LDOK] is set.

Parameters

- base – EQDC peripheral base address
- u32PositionComp2Value – Position modulus value

static inline void EQDC_SetPositionCompare3Value(EQDC_Type *base, uint32_t u32PositionComp3Value)

Set position counter compare 3 value.

Set the position counter compare 3 value (UCOMP3, LCOMP3). After writing values to the UCOMP3 and LCOMP3 registers, the values are "buffered" into outer-set registers temporarily. Values will be loaded into inner-set registers and take effect using the following two methods:

a. If CTRL2[LDMODE] is 1, "buffered" values are loaded into inner-set and take effect at the next roll-over or roll-under if CTRL[LDOK] is set.

b. If CTRL2[LDMODE] is 0, "buffered" values are loaded into inner-set and take effect immediately when CTRL[LDOK] is set.

Parameters

- base – EQDC peripheral base address
- u32PositionComp3Value – Position modulus value

static inline uint32_t EQDC_GetPosition(EQDC_Type *base)

Get the current position counter's value.

Parameters

- base – EQDC peripheral base address.

Returns

Current position counter's value.

static inline uint32_t EQDC_GetHoldPosition(EQDC_Type *base)

Get the hold position counter's value.

The position counter (POS or UPOS, LPOS) value is loaded to hold position (POSH or UPOSH, LPOSH) when:

a. Position register (POS or UPOS, LPOS), or position difference register (POSD), or revolution register (REV) is read.

b. TRIGGER happens and TRIGGER is enabled to update the hold registers.

Parameters

- base – EQDC peripheral base address.

Returns

Hold position counter's value.

static inline uint32_t EQDC_GetHoldPosition1(EQDC_Type *base)

Get the hold position counter1's value.

The Upper Position Counter Hold Register 1(UPOSH1) shares the same address with UCOMP1. When read, this register means the value of UPOSH1, which is the upper 16 bits of POSH1. The Lower Position Counter Hold Register 1(LPOSH1) shares the same address with LCOMP1. When read, this register means the value of LPOSH1, which is the lower 16 bits of POSH1. Position counter is captured into POSH1 on the rising edge of ICAP[1].

Parameters

- base – EQDC peripheral base address.

Returns

Hold position counter1's value.

static inline uint32_t EQDC_GetHoldPosition2(EQDC_Type *base)

Get the hold position counter2's value.

The Upper Position Counter Hold Register 2(UPOSH2) shares the same address with UCOMP2. When read,this register means the value of UPOSH2, which is the upper 16 bits of POSH2. The Lower Position Counter Hold Register 2(LPOSH2) shares the same address with LCOMP2. When read, this register means the value of LPOSH2, which is the lower 16 bits of POSH2. Position counter is captured into POSH2 on the rising edge of ICAP[2].

Parameters

- base – EQDC peripheral base address.

Returns

Hold position counter2's value.

static inline uint32_t EQDC_GetHoldPosition3(EQDC_Type *base)

Get the hold position counter3's value.

The Upper Position Counter Hold Register 3(UPOSH3) shares the same address with UCOMP3. When read,this register means the value of UPOSH3, which is the upper 16 bits of POSH3. The Lower Position Counter Hold Register 3(LPOSH3) shares the same address with LCOMP3. When read, this register means the value of LPOSH3, which is the lower 16 bits of POSH3. Position counter is captured into POSH3 on the rising edge of ICAP[3].

Parameters

- base – EQDC peripheral base address.

Returns

Hold position counter3's value.

static inline uint16_t EQDC_GetPositionDifference(EQDC_Type *base)

Get the position difference counter's value.

Parameters

- base – EQDC peripheral base address.

Returns

The position difference counter's value.

static inline uint16_t EQDC_GetHoldPositionDifference(EQDC_Type *base)

Get the hold position difference counter's value.

The position difference (POSD) value is loaded to hold position difference (POSDH) when:

a. Position register (POS or UPOS, LPOS), or position difference register (POSD), or revolution register (REV) is read. When Period Measurement is enabled (CTRL3[PMEN] = 1), POSDH will only be udpated when reading POSD.

b. TRIGGER happens and TRIGGER is enabled to update the hold registers.

Parameters

- base – EQDC peripheral base address.

Returns

Hold position difference counter's value.

static inline uint16_t EQDC_GetRevolution(EQDC_Type *base)

Get the revolution counter's value.

Get the revolution counter (REV) value.

Parameters

- base – EQDC peripheral base address.

Returns
The revolution counter's value.

static inline uint16_t EQDC_GetHoldRevolution(EQDC_Type *base)

Get the hold revolution counter's value.

The revolution counter (REV) value is loaded to hold revolution (REVH) when:

a. Position register (POS or UPOS, LPOS), or position difference register (POSD), or revolution register (REV) is read.

b. TRIGGER happens and TRIGGER is enabled to update the hold registers.

Parameters

- base – EQDC peripheral base address.

Returns
Hold position revolution counter's value.

static inline uint16_t EQDC_GetLastEdgeTime(EQDC_Type *base)

Get the last edge time.

Last edge time (LASTEDGE) is the time since the last edge occurred on PHASEA or PHASEB. The last edge time register counts up using the peripheral clock after prescaler. Any edge on PHASEA or PHASEB will reset this register to 0 and start counting. If the last edge timer count reaches 0xffff, the counting will stop in order to prevent an overflow.Counting will continue when an edge occurs on PHASEA or PHASEB.

Parameters

- base – EQDC peripheral base address.

Returns
The last edge time.

static inline uint16_t EQDC_GetHoldLastEdgeTime(EQDC_Type *base)

Get the hold last edge time.

The hold of last edge time(LASTEDGEH) is update to last edge time(LASTEDGE) when the position difference register register (POSD) is read.

Parameters

- base – EQDC peripheral base address.

Returns
Hold of last edge time.

static inline uint16_t EQDC_GetPositionDifferencePeriod(EQDC_Type *base)

Get the Position Difference Period counter value.

The Position Difference Period counter (POSDPER) counts up using the prescaled peripheral clock. When reading the position difference register(POSD), the last edge time (LASTEDGE) will be loaded to position difference period counter(POSDPER). If the POSDPER count reaches 0xffff, the counting will stop in order to prevent an overflow. Counting will continue when an edge occurs on PHASEA or PHASEB.

Parameters

- base – EQDC peripheral base address.

Returns
The position difference period counter value.

static inline uint16_t EQDC_GetBufferedPositionDifferencePeriod(EQDC_Type *base)

Get buffered Position Difference Period counter value.

The Bufferd Position Difference Period (POSDPERBFR) value is updated with the position difference period counter(POSDPER) when any edge occurs on PHASEA or PHASEB.

Parameters

- base – EQDC peripheral base address.

Returns

The buffered position difference period counter value.

static inline uint16_t EQDC_GetHoldPositionDifferencePeriod(EQDC_Type *base)

Get Hold Position Difference Period counter value.

The hold position difference period(POSDPERH) is updated with the value of buffered position difference period(POSDPERBFR) when the position difference(POSD) register is read.

Parameters

- base – EQDC peripheral base address.

Returns

The hold position difference period counter value.

enum _eqdc_status_flags

EQDC status flags, these flags indicate the counter's events. .

Values:

enumerator kEQDC_HomeEnableTransitionFlag

HOME/ENABLE signal transition occured.

enumerator kEQDC_IndexPresetPulseFlag

INDEX/PRESET pulse occured.

enumerator kEQDC_WatchdogTimeoutFlag

Watchdog timeout occured.

enumerator kEQDC_SimultPhaseChangeFlag

Simultaneous change of PHASEA and PHASEB occured.

enumerator kEQDC_CountDirectionChangeFlag

Count direction change interrupt enable.

enumerator kEQDC_PositionRollOverFlag

Position counter rolls over from 0xFFFFFFFF to 0, or from MOD value to INIT value.

enumerator kEQDC_PositionRollUnderFlag

Position register roll under from 0 to 0xFFFFFFFF, or from INIT value to MOD value.

enumerator kEQDC_PositionCompare0Flag

Position counter match the COMP0 value.

enumerator kEQDC_PositionCompare1Flag

Position counter match the COMP1 value.

enumerator kEQDC_PositionCompare2Flag
Position counter match the COMP2 value.

enumerator kEQDC_PositionCompare3Flag
Position counter match the COMP3 value.

enumerator kEQDC_StatusAllFlags

enum _eqdc_signal_status
Signal status, these flags indicate the raw and filtered input signal status. .
Values:

enumerator kEQDC_SignalStatusRawHomeEnable
Raw HOME/ENABLE input.

enumerator kEQDC_SignalStatusRawIndexPreset
Raw INDEX/PRESET input.

enumerator kEQDC_SignalStatusRawPhaseB
Raw PHASEB input.

enumerator kEQDC_SignalStatusRawPhaseA
Raw PHASEA input.

enumerator kEQDC_SignalStatusFilteredHomeEnable
The filtered HOME/ENABLE input.

enumerator kEQDC_SignalStatusFilteredIndexPreset
The filtered INDEX/PRESET input.

enumerator kEQDC_SignalStatusFilteredPhaseB
The filtered PHASEB input.

enumerator kEQDC_SignalStatusFilteredPhaseA
The filtered PHASEA input.

enumerator kEQDC_SignalStatusPositionCompare0Flag
Position Compare 0 Flag Output.

enumerator kEQDC_SignalStatusPositionCompare1Flag
Position Compare 1 Flag Output.

enumerator kEQDC_SignalStatusPositionCompare2Flag
Position Compare 2 Flag Output.

enumerator kEQDC_SignalStatusPositionCompare3Flag
Position Compare 3 Flag Output.

enumerator kEQDC_SignalStatusCountDirectionFlagHold
Count Direction Flag Hold.

enumerator kEQDC_SignalStatusCountDirectionFlag
Count Direction Flag Output.

enumerator kEQDC_SignalStatusAllFlags

enum _eqdc_interrupt_enable
Interrupt enable/disable mask. .
Values:

enumerator kEQDC_HomeEnableTransitionInterruptEnable
HOME/ENABLE signal transition interrupt enable.

enumerator kEQDC_IndexPresetPulseInterruptEnable
INDEX/PRESET pulse interrupt enable.

enumerator kEQDC_WatchdogTimeoutInterruptEnable
Watchdog timeout interrupt enable.

enumerator kEQDC_SimultPhaseChangeInterruptEnable
Simultaneous PHASEA and PHASEB change interrupt enable.

enumerator kEQDC_CountDirectionChangeInterruptEnable
Count direction change interrupt enable.

enumerator kEQDC_PositionRollOverInterruptEnable
Roll-over interrupt enable.

enumerator kEQDC_PositionRollUnderInterruptEnable
Roll-under interrupt enable.

enumerator kEQDC_AllInterruptEnable

enum _eqdc_home_enable_init_pos_counter_mode
Define HOME/ENABLE signal's trigger mode.
Values:

enumerator kEQDC_HomeInitPosCounterDisabled
Don't use HOME/ENABLE signal to initialize the position counter.

enumerator kEQDC_HomeInitPosCounterOnRisingEdge
Use positive going edge to trigger initialization of position counters.

enumerator kEQDC_HomeInitPosCounterOnFallingEdge
Use negative going edge to trigger initialization of position counters.

enum _eqdc_index_preset_init_pos_counter_mode

Define INDEX/PRESET signal's trigger mode.

Values:

enumerator kEQDC_IndexInitPosCounterDisabled

INDEX/PRESET pulse does not initialize the position counter.

enumerator kEQDC_IndexInitPosCounterOnRisingEdge

Use INDEX/PRESET pulse rising edge to initialize position counter.

enumerator kEQDC_IndexInitPosCounterOnFallingEdge

Use INDEX/PRESET pulse falling edge to initialize position counter.

enum _eqdc_operate_mode

Define type for decoder opertion mode.

The Quadrature Decoder operates in following 4 operation modes: 1.Quadrature Decode(QDC) Operation Mode (CTRL[PH1] = 0,CTRL2[OPMODE] = 0) In QDC operation mode, Module uses PHASEA, PHASEB, INDEX, HOME, TRIGGER and ICAP[3:1] to decode the PHASEA and PHASEB signals from Speed/Position sensor. 2.Quadrature Count(QCT) Operation Mode (CTRL[PH1] = 0,CTRL2[OPMODE] = 1) In QCT operation mode, Module uses PHASEA, PHASEB, PRESET, ENABLE, TRIGGER and ICAP[3:1] to count the PHASEA and PHASEB signals from Speed/Position sensor. 3.Single Phase Decode(PH1DC) Operation Mode (CTRL[PH1] = 1,CTRL2[OPMODE] = 0) In PH1DC operation mode, the module uses PHASEA, PHASEB, INDEX, HOME, TRIGGER and ICAP[3:1] to decode the PHASEA and PHASEB signals from Speed/Position sensor. 4.Single Phase Count(PH1CT) Operation Mode (CTRL[PH1] = 1,CTRL2[OPMODE] = 1) In PH1CT operation mode, the module uses PHASEA, PHASEB, PRESET, ENABLE, TRIGGER and ICAP[3:1] to count the PHASEA and PHASEB signals from Speed/Position sensor.

Values:

enumerator kEQDC_QuadratureDecodeOperationMode

Use standard quadrature decoder with PHASEA/PHASEB, INDEX/HOME.

enumerator kEQDC_QuadratureCountOperationMode

Use quadrature count operation mode with PHASEA/PHASEB, PRESET/ENABLE.

enumerator kEQDC_SinglePhaseDecodeOperationMode

Use single phase quadrature decoder with PHASEA/PHASEB, INDEX/HOME.

enumerator kEQDC_SinglePhaseCountOperationMode

Use single phase count decoder with PHASEA/PHASEB, PRESET/ENABLE.

enum _eqdc_count_mode

Define type for decoder count mode.

In decode mode, it uses the standard quadrature decoder with PHASEA and PHASEB, PHASEA = 0 and PHASEB = 0 mean reverse direction.

- If PHASEA leads PHASEB, then motion is in the positive direction.
- If PHASEA trails PHASEB,then motion is in the negative direction. In single phase mode, there are three count modes:

- In Signed Count mode (Single Edge). Both position counter (POS) and position difference counter (POSD) count on the input PHASEA rising edge while the input PHASEB provides the selected position counter direction (up/down). If CTRL[REV] is 1, then the position counter will count in the opposite direction.
- In Signed Count mode (double edge), both position counter (POS) and position difference counter (POSD) count the input PHASEA on both rising edge and falling edge while the input PHASEB provides the selected position counter direction (up/down).
- In UP/DOWN Pulse Count mode. Both position counter (POS) and position difference counter (POSD) count in the up direction when input PHASEA rising edge occurs. Both counters count in the down direction when input PHASEB rising edge occurs. If CTRL[REV] is 1, then the position counter will count in the opposite direction.

Values:

enumerator kEQDC_QuadratureX4

Active on kEQDC_QuadratureDecodeOperationMode/kEQDC_QuadratureCountOperationMode.

enumerator kEQDC_QuadratureX2

Active on kEQDC_QuadratureDecodeOperationMode/kEQDC_QuadratureCountOperationMode.

enumerator kEQDC_QuadratureX1

Active on kEQDC_QuadratureDecodeOperationMode/kEQDC_QuadratureCountOperationMode.

enumerator kEQDC_UpDownPulseCount

Active on kEQDC_SinglePhaseDecodeOperationMode/kEQDC_SinglePhaseCountOperationMode.

enumerator kEQDC_SignedCountDoubleEdge

Active on kEQDC_SinglePhaseDecodeOperationMode/kEQDC_SinglePhaseCountOperationMode.

enumerator kEQDC_SignedCountSingleEdge

Active on kEQDC_SinglePhaseDecodeOperationMode/kEQDC_SinglePhaseCountOperationMode.

enum _eqdc_output_pulse_mode

Define type for the condition of POSMATCH pulses.

Values:

enumerator kEQDC_OutputPulseOnCounterEqualCompare

POSMATCH pulses when a match occurs between the position counters (POS) and the compare value (UCOMPx/LCOMPx)(x range is 0-3).

enumerator kEQDC_OutputPulseOnReadingPositionCounter

POSMATCH pulses when reading position counter(POS and LPOS), revolution counter(REV), position difference counter(POSD).

enum _eqdc_revolution_count_condition

Define type for determining how the revolution counter (REV) is incremented/decremented.

Values:

enumerator kEQDC_RevolutionCountOnIndexPulse

Use INDEX pulse to increment/decrement revolution counter.

enumerator kEQDC_RevolutionCountOnRollOverModulus

Use modulus counting roll-over/under to increment/decrement revolution counter.

enum _eqdc_filter_sample_count

Input Filter Sample Count.

The Input Filter Sample Count represents the number of consecutive samples that must agree, before the input filter accepts an input transition

Values:

enumerator kEQDC_Filter3Samples

3 samples.

enumerator kEQDC_Filter4Samples

4 samples.

enumerator kEQDC_Filter5Samples

5 samples.

enumerator kEQDC_Filter6Samples

6 samples.

enumerator kEQDC_Filter7Samples

7 samples.

enumerator kEQDC_Filter8Samples

8 samples.

enumerator kEQDC_Filter9Samples

9 samples.

enumerator kEQDC_Filter10Samples

10 samples.

enum _eqdc_count_direction_flag

Count direction.

Values:

enumerator kEQDC_CountDirectionDown

Last count was in down direction.

enumerator kEQDC_CountDirectionUp

Last count was in up direction.

enum _eqdc_prescaler

Prescaler used by Last Edge Time (LASTEDGE) and Position Difference Period Counter (POSDPER).

Values:

enumerator kEQDC_Prescaler1
Prescaler value 1.

enumerator kEQDC_Prescaler2
Prescaler value 2.

enumerator kEQDC_Prescaler4
Prescaler value 4.

enumerator kEQDC_Prescaler8
Prescaler value 8.

enumerator kEQDC_Prescaler16
Prescaler value 16.

enumerator kEQDC_Prescaler32
Prescaler value 32.

enumerator kEQDC_Prescaler64
Prescaler value 64.

enumerator kEQDC_Prescaler128
Prescaler value 128.

enumerator kEQDC_Prescaler256
Prescaler value 256.

enumerator kEQDC_Prescaler512
Prescaler value 512.

enumerator kEQDC_Prescaler1024
Prescaler value 1024.

enumerator kEQDC_Prescaler2048
Prescaler value 2048.

enumerator kEQDC_Prescaler4096
Prescaler value 4096.

enumerator kEQDC_Prescaler8192
Prescaler value 8192.

enumerator kEQDC_Prescaler16384
Prescaler value 16384.

enumerator kEQDC_Prescaler32768
Prescaler value 32768.

typedef enum *_eqdc_home_enable_init_pos_counter_mode*
eqdc_home_enable_init_pos_counter_mode_t

Define HOME/ENABLE signal's trigger mode.

typedef enum *_eqdc_index_preset_init_pos_counter_mode*
eqdc_index_preset_init_pos_counter_mode_t

Define INDEX/PRESET signal's trigger mode.

typedef enum *_eqdc_operate_mode* eqdc_operate_mode_t

Define type for decoder opertion mode.

The Quadrature Decoder operates in following 4 operation modes: 1.Quadrature Decode(QDC) Operation Mode (CTRL[PH1] = 0,CTRL2[OPMODE] = 0) In QDC operation mode, Module uses PHASEA, PHASEB, INDEX, HOME, TRIGGER and ICAP[3:1] to decode the PHASEA and PHASEB signals from Speed/Position sensor. 2.Quadrature Count(QCT) Operation Mode (CTRL[PH1] = 0,CTRL2[OPMODE] = 1) In QCT operation mode, Module uses PHASEA, PHASEB, PRESET, ENABLE, TRIGGER and ICAP[3:1] to count the PHASEA and PHASEB signals from Speed/Position sensor. 3.Single Phase Decode(PH1DC) Operation Mode (CTRL[PH1] = 1,CTRL2[OPMODE] = 0) In PH1DC operation mode, the module uses PHASEA, PHASEB, INDEX, HOME, TRIGGER and ICAP[3:1] to decode the PHASEA and PHASEB signals from Speed/Position sensor. 4.Single Phase Count(PH1CT) Operation Mode (CTRL[PH1] = 1,CTRL2[OPMODE] = 1) In PH1CT operation mode, the module uses PHASEA, PHASEB, PRESET, ENABLE, TRIGGER and ICAP[3:1] to count the PHASEA and PHASEB signals from Speed/Position sensor.

typedef enum *_eqdc_count_mode* eqdc_count_mode_t

Define type for decoder count mode.

In decode mode, it uses the standard quadrature decoder with PHASEA and PHASEB, PHASEA = 0 and PHASEB = 0 mean reverse direction.

- If PHASEA leads PHASEB, then motion is in the positive direction.
- If PHASEA trails PHASEB,then motion is in the negative direction. In single phase mode, there are three count modes:
- In Signed Count mode (Single Edge). Both position counter (POS) and position difference counter (POSD) count on the input PHASEA rising edge while the input PHASEB provides the selected position counter direction (up/down). If CTRL[REV] is 1, then the position counter will count in the opposite direction.
- In Signed Count mode (double edge), both position counter (POS) and position difference counter (POSD) count the input PHASEA on both rising edge and falling edge while the input PHASEB provides the selected position counter direction (up/down).
- In UP/DOWN Pulse Count mode. Both position counter (POS) and position difference counter (POSD) count in the up direction when input PHASEA rising edge occurs. Both counters count in the down direction when input PHASEB rising edge occurs. If CTRL[REV] is 1, then the position counter will count in the opposite direction.

typedef enum *_eqdc_output_pulse_mode* eqdc_output_pulse_mode_t

Define type for the condition of POSMATCH pulses.

typedef enum *_eqdc_revolution_count_condition* eqdc_revolution_count_condition_t

Define type for determining how the revolution counter (REV) is incremented/decremented.

typedef enum *_eqdc_filter_sample_count* eqdc_filter_sample_count_t

Input Filter Sample Count.

The Input Filter Sample Count represents the number of consecutive samples that must agree, before the input filter accepts an input transition

typedef enum *_eqdc_count_direction_flag* eqdc_count_direction_flag_t

Count direction.

typedef enum *_eqdc_prescaler* eqdc_prescaler_t

Prescaler used by Last Edge Time (LASTEDGE) and Position Difference Period Counter (POSDPER).

typedef struct *_eqdc_config* eqdc_config_t

Define user configuration structure for EQDC module.

FSL_EQDC_DRIVER_VERSION

EQDC_CTRL_W1C_FLAGS

W1C bits in EQDC CTRL registers.

EQDC_INTCTRL_W1C_FLAGS

W1C bits in EQDC INTCTRL registers.

EQDC_CTRL_INT_EN

Interrupt enable bits in EQDC CTRL registers.

EQDC_INTCTRL_INT_EN

Interrupt enable bits in EQDC INTCTRL registers.

EQDC_CTRL_INT_FLAGS

Interrupt flag bits in EQDC CTRL registers.

EQDC_INTCTRL_INT_FLAGS

Interrupt flag bits in EQDC INTCTRL registers.

struct _eqdc_config

#include <fsl_eqdc.h> Define user configuration structure for EQDC module.

Public Members

bool enableReverseDirection

Enable reverse direction counting.

bool countOnce

Selects modulo loop or one shot counting mode.

bool enableDma

Enable DMA for new written buffer values of COMPx/INIT/MOD(x range is 0-3)

bool bufferedRegisterLoadMode

selects the loading time point of the buffered compare registers UCOMPx/LCOMPx, x=0~3, initial register (UINIT/LINIT), and modulus register (UMOD/LMOD).

bool enableTriggerInitPositionCounter

Initialize position counter with initial register(UINIT, LINIT) value on TRIGGER's rising edge.

bool enableIndexInitPositionCounter

Enables the feature that the position counter to be initialized by Index Event Edge Mark.

This option works together with *_eqdc_index_preset_init_pos_counter_mode* and *enableReverseDirection*; If enabled, the behavior is like this:

When PHA leads PHB (Clockwise): If *_eqdc_index_preset_init_pos_counter_mode* is *kEQDC_IndexInitPosCounterOnRisingEdge*, then INDEX rising edge reset position counter. If *_eqdc_index_preset_init_pos_counter_mode* is *kEQDC_IndexInitPosCounterOnFallingEdge*, then INDEX falling edge reset position counter. If *enableReverseDirection* is false, then Reset position counter to initial value. If *enableReverseDirection* is true, then reset position counter to modulus value.

When PHA lags PHB (Counter Clockwise): If *_eqdc_index_preset_init_pos_counter_mode* is *kEQDC_IndexInitPosCounterOnRisingEdge*, then INDEX falling edge reset position counter. If *_eqdc_index_preset_init_pos_counter_mode* is *kEQDC_IndexInitPosCounterOnFallingEdge*, then INDEX rising edge reset position counter. If *enableReverseDirection* is false, then Reset position counter to modulus value. If *enableReverseDirection* is true, then reset position counter to initial value.

bool enableTriggerClearPositionRegisters

Clear position counter(POS), revolution counter(REV), position difference counter (POSD) on TRIGGER's rising edge.

bool enableTriggerHoldPositionRegisters

Load position counter(POS), revolution counter(REV), position difference counter (POSD) values to hold registers on TRIGGER's rising edge.

bool filterPhaseA

Filter operation on PHASEA input, when write 1, it means filter for PHASEA input is bypassed.

bool filterPhaseB

Filter operation on PHASEB input, when write 1, it means filter for PHASEB input is bypassed.

bool filterIndPre

Filter operation on INDEX/PRESET input, when write 1, it means filter for INDEX/PRESET input is bypassed.

bool filterHomEna

Filter operation on HOME/ENABLE input, when write 1, it means filter for HOME/ENABLE input is bypassed.

bool enableWatchdog

Enable the watchdog to detect if the target is moving or not.

uint16_t watchdogTimeoutValue

Watchdog timeout count value. It stores the timeout count for the quadrature decoder module watchdog timer.

eqdc_prescaler_t prescaler

Prescaler.

bool filterClockSourceselection

Filter Clock Source selection.

eqdc_filter_sample_count_t filterSampleCount

Input Filter Sample Count. This value should be chosen to reduce the probability of noisy samples causing an incorrect transition to be recognized. The value represent the number of consecutive samples that must agree prior to the input filter accepting an input transition.

uint8_t filterSamplePeriod

Input Filter Sample Period. This value should be set such that the sampling period is larger than the period of the expected noise. This value represents the sampling period (in IPBus clock cycles) of the decoder input signals. The available range is 0 - 255.

eqdc_operate_mode_t operateMode

Selects operation mode.

eqdc_count_mode_t countMode

Selects count mode.

eqdc_home_enable_init_pos_counter_mode_t homeEnableInitPosCounterMode

Select how HOME/Enable signal used to initialize position counters.

eqdc_index_preset_init_pos_counter_mode_t indexPresetInitPosCounterMode

Select how INDEX/Preset signal used to initialize position counters.

eqdc_output_pulse_mode_t outputPulseMode

The condition of POSMATCH pulses.

uint32_t positionCompareValue[4]

Position compare 0 ~ 3 value. The available value is a 32-bit number.

eqdc_revolution_count_condition_t revolutionCountCondition

Revolution Counter Modulus Enable.

uint32_t positionModulusValue

Position modulus value. The available value is a 32-bit number.

uint32_t positionInitialValue

Position initial value. The available value is a 32-bit number.

uint32_t positionCounterValue

Position counter value. When Modulo mode enabled, the positionCounterValue should be in the range of *positionInitialValue* and *positionModulusValue*.

bool enablePeriodMeasurement

Enable period measurement. When enabled, the position difference hold register (POSDH) is only updated when position difference register (POSD) is read.

uint16_t enabledInterruptsMask

Mask of interrupts to be enabled, should be OR'ed value of *_eqdc_interrupt_enable*.

2.12 ERM: error recording module

void ERM_Init(ERM_Type *base)

ERM module initialization function.

Parameters

- base – ERM base address.

void ERM_Deinit(ERM_Type *base)

De-initializes the ERM.

static inline void ERM_EnableInterrupts(ERM_Type *base, uint32_t channel, uint32_t mask)

ERM enable interrupts.

Parameters

- base – ERM peripheral base address.
- channel – memory channel.
- mask – single correction interrupt or non-correction interrupt enable to disable for one specific memory region. Refer to "_erm_interrupt_enable" enumeration.

static inline void ERM_DisableInterrupts(ERM_Type *base, uint32_t channel, uint32_t mask)

ERM module disable interrupts.

Parameters

- base – ERM base address.
- channel – memory channel.
- mask – single correction interrupt or non-correction interrupt enable to disable for one specific memory region. Refer to "_erm_interrupt_enable" enumeration.

static inline uint32_t ERM_GetInterruptStatus(ERM_Type *base, uint32_t channel)

Gets ERM interrupt flags.

Parameters

- base – ERM peripheral base address.

Returns

ERM event flags.

static inline void ERM_ClearInterruptStatus(ERM_Type *base, uint32_t channel, uint32_t mask)

ERM module clear interrupt status flag.

Parameters

- base – ERM base address.
- mask – event flag to clear. Refer to "_erm_interrupt_flag" enumeration.

uint32_t ERM_GetMemoryErrorAddr(ERM_Type *base, uint32_t channel)

ERM get memory error absolute address, which capturing the address of the last ECC event in Memory n.

Parameters

- base – ERM base address.
- channel – memory channel.

Return values

memory – error absolute address.

FSL_ERM_DRIVER_VERSION

Driver version.

ERM interrupt configuration structure, default settings all disabled, _erm_interrupt_enable.

This structure contains the settings for all of the ERM interrupt configurations.

Values:

enumerator kERM_SingleCorrectionIntEnable

Single Correction Interrupt Notification enable.

enumerator kERM_NonCorrectableIntEnable

Non-Correction Interrupt Notification enable.

enumerator kERM_AllInterruptsEnable

All Interrupts enable

ERM interrupt status, _erm_interrupt_flag.

This provides constants for the ERM event status for use in the ERM functions.

Values:

enumerator kERM_SingleBitCorrectionIntFlag

Single-Bit Correction Event.

enumerator kERM_NonCorrectableErrorIntFlag

Non-Correctable Error Event.

enumerator kERM_AllIntsFlag

All Events.

2.13 FGPIO Driver

2.14 FlexCAN: Flex Controller Area Network Driver

2.15 FlexCAN Driver

bool FLEXCAN_IsInstanceHasFDMode(CAN_Type *base)

Determine whether the FlexCAN instance support CAN FD mode at run time.

Note: Use this API only if different soc parts share the SOC part name macro define. Otherwise, a different SOC part name can be used to determine at compile time whether the FlexCAN instance supports CAN FD mode or not. If need use this API to determine if CAN FD mode is supported, the FLEXCAN_Init function needs to be executed first, and then call this API and use the return to value determines whether to supports CAN FD mode, if return true, continue calling FLEXCAN_FDInit to enable CAN FD mode.

Parameters

- base – FlexCAN peripheral base address.

Returns

return TRUE if instance support CAN FD mode, FALSE if instance only support classic CAN (2.0) mode.

uint32_t FLEXCAN_GetFDMailboxOffset(CAN_Type *base, uint8_t mbIdx)

Get Mailbox offset number by dword.

This function gets the offset number of the specified mailbox. Mailbox is not consecutive between memory regions when payload is not 8 bytes so need to calculate the specified mailbox address. For example, in the first memory region, MB[0].CS address is 0x4002_4080. For 32 bytes payload frame, the second mailbox is ((1/12)*512 + 1%12*40)/4 = 10, meaning 10 dword after the 0x4002_4080, which is actually the address of mailbox MB[1].CS.

Parameters

- base – FlexCAN peripheral base address.
- mbIdx – Mailbox index.

Returns

Mailbox address offset in word.

status_t FLEXCAN_EnterFreezeMode(CAN_Type *base)

Enter FlexCAN Freeze Mode.

This function makes the FlexCAN work under Freeze Mode.

Parameters

- base – FlexCAN peripheral base address.

Returns

kStatus_Success Enter Freeze Mode successful kStatus_Timeout Timeout when wait for Freeze Mode Acknowledge

status_t FLEXCAN_ExitFreezeMode(CAN_Type *base)

Exit FlexCAN Freeze Mode.

This function makes the FlexCAN leave Freeze Mode.

Parameters

- base – FlexCAN peripheral base address.

Returns

kStatus_Success Enter Freeze Mode successful kStatus_Timeout Timeout when wait for Freeze Mode Acknowledge

uint32_t FLEXCAN_GetInstance(CAN_Type *base)

Get the FlexCAN instance from peripheral base address.

Parameters

- base – FlexCAN peripheral base address.

Returns

FlexCAN instance.

bool FLEXCAN_CalculateImprovedTimingValues(CAN_Type *base, uint32_t bitRate, uint32_t sourceClock_Hz, *flexcan_timing_config_t* *pTimingConfig)

Calculates the improved timing values by specific bit Rates for classical CAN.

This function use to calculates the Classical CAN timing values according to the given bit rate. The Calculated timing values will be set in CTRL1/CBT/ENCBT register. The calculation is based on the recommendation of the CiA 301 v4.2.0 and previous version document.

Parameters

- base – FlexCAN peripheral base address.
- bitRate – The classical CAN speed in bps defined by user, should be less than or equal to 1Mbps.
- sourceClock_Hz – The Source clock frequency in Hz.
- pTimingConfig – Pointer to the FlexCAN timing configuration structure.

Returns

TRUE if timing configuration found, FALSE if failed to find configuration.

void FLEXCAN_Init(CAN_Type *base, const *flexcan_config_t* *pConfig, uint32_t sourceClock_Hz)

Initializes a FlexCAN instance.

This function initializes the FlexCAN module with user-defined settings. This example shows how to set up the flexcan_config_t parameters and how to call the FLEXCAN_Init function by passing in these parameters.

```
flexcan_config_t flexcanConfig;
flexcanConfig.clkSrc                 = kFLEXCAN_ClkSrc0;
flexcanConfig.bitRate                = 1000000U;
flexcanConfig.maxMbNum               = 16;
flexcanConfig.enableLoopBack         = false;
flexcanConfig.enableSelfWakeup       = false;
flexcanConfig.enableIndividMask      = false;
flexcanConfig.enableDoze             = false;
flexcanConfig.disableSelfReception   = false;
flexcanConfig.enableListenOnlyMode   = false;
flexcanConfig.timingConfig           = timingConfig;
FLEXCAN_Init(CAN0, &flexcanConfig, 40000000UL);
```

Parameters

- base – FlexCAN peripheral base address.
- pConfig – Pointer to the user-defined configuration structure.
- sourceClock_Hz – FlexCAN Protocol Engine clock source frequency in Hz.

bool FLEXCAN_FDCalculateImprovedTimingValues(CAN_Type *base, uint32_t bitRate, uint32_t bitRateFD, uint32_t sourceClock_Hz, *flexcan_timing_config_t* *pTimingConfig)

Calculates the improved timing values by specific bit rates for CANFD.

This function use to calculates the CANFD timing values according to the given nominal phase bit rate and data phase bit rate. The Calculated timing values will be set in CBT/ENCBT and FDCBT/EDCBT registers. The calculation is based on the recommendation of the CiA 1301 v1.0.0 document.

Parameters

- base – FlexCAN peripheral base address.
- bitRate – The CANFD bus control speed in bps defined by user.
- bitRateFD – The CAN FD data phase speed in bps defined by user. Equal to bitRate means disable bit rate switching.
- sourceClock_Hz – The Source clock frequency in Hz.
- pTimingConfig – Pointer to the FlexCAN timing configuration structure.

Returns

TRUE if timing configuration found, FALSE if failed to find configuration

void FLEXCAN_FDInit(CAN_Type *base, const *flexcan_config_t* *pConfig, uint32_t sourceClock_Hz, *flexcan_mb_size_t* dataSize, bool brs)

Initializes a FlexCAN instance.

This function initializes the FlexCAN module with user-defined settings. This example shows how to set up the flexcan_config_t parameters and how to call the FLEXCAN_FDInit function by passing in these parameters.

```
flexcan_config_t flexcanConfig;
flexcanConfig.clkSrc                 = kFLEXCAN_ClkSrc0;
flexcanConfig.bitRate                = 1000000U;
flexcanConfig.bitRateFD              = 2000000U;
flexcanConfig.maxMbNum               = 16;
flexcanConfig.enableLoopBack         = false;
flexcanConfig.enableSelfWakeup       = false;
flexcanConfig.enableIndividMask      = false;
flexcanConfig.disableSelfReception = false;
flexcanConfig.enableListenOnlyMode = false;
flexcanConfig.enableDoze             = false;
flexcanConfig.timingConfig           = timingConfig;
FLEXCAN_FDInit(CAN0, &flexcanConfig, 80000000UL, kFLEXCAN_16BperMB, true);
```

Parameters

- base – FlexCAN peripheral base address.
- pConfig – Pointer to the user-defined configuration structure.
- sourceClock_Hz – FlexCAN Protocol Engine clock source frequency in Hz.
- dataSize – FlexCAN Message Buffer payload size. The actual transmitted or received CAN FD frame data size needs to be less than or equal to this value.
- brs – True if bit rate switch is enabled in FD mode.

void FLEXCAN_Deinit(CAN_Type *base)

De-initializes a FlexCAN instance.

This function disables the FlexCAN module clock and sets all register values to the reset value.

Parameters

- base – FlexCAN peripheral base address.

void FLEXCAN_GetDefaultConfig(*flexcan_config_t* *pConfig)

Gets the default configuration structure.

This function initializes the FlexCAN configuration structure to default values. The default values are as follows. flexcanConfig->clkSrc = kFLEXCAN_ClkSrc0; flexcanConfig->bitRate = 1000000U; flexcanConfig->bitRateFD = 2000000U; flexcanConfig->maxMbNum = 16; flexcanConfig->enableLoopBack = false; flexcanConfig->enableSelfWakeup = false; flexcanConfig->enableIndividMask = false; flexcanConfig->disableSelfReception = false; flexcanConfig->enableListenOnlyMode = false; flexcanConfig->enableDoze = false; flexcanConfig->enablePretendedeNetworking = false; flexcanConfig->enableMemoryErrorControl = true; flexcanConfig->enableNonCorrectableErrorEnterFreeze = true; flexcanConfig->enableTransceiverDelayMeasure = true; flexcanConfig->enableRemoteRequestFrameStored = true; flexcanConfig->payloadEndianness = kFLEXCAN_bigEndian; flexcanConfig.timingConfig = timingConfig;

Parameters

- pConfig – Pointer to the FlexCAN configuration structure.

void FLEXCAN_SetTimingConfig(CAN_Type *base, const *flexcan_timing_config_t* *pConfig)

Sets the FlexCAN classical CAN protocol timing characteristic.

This function gives user settings to classical CAN or CAN FD nominal phase timing characteristic. The function is for an experienced user. For less experienced users, call the *FLEXCAN_SetBitRate()* instead.

Note: Calling *FLEXCAN_SetTimingConfig()* overrides the bit rate set in *FLEXCAN_Init()* or *FLEXCAN_SetBitRate()*.

Parameters

- base – FlexCAN peripheral base address.
- pConfig – Pointer to the timing configuration structure.

status_t FLEXCAN_SetBitRate(CAN_Type *base, uint32_t sourceClock_Hz, uint32_t bitRate_Bps)

Set bit rate of FlexCAN classical CAN frame or CAN FD frame nominal phase.

This function set the bit rate of classical CAN frame or CAN FD frame nominal phase base on *FLEXCAN_CalculateImprovedTimingValues()* API calculated timing values.

Note: Calling *FLEXCAN_SetBitRate()* overrides the bit rate set in *FLEXCAN_Init()*.

Parameters

- base – FlexCAN peripheral base address.
- sourceClock_Hz – Source Clock in Hz.
- bitRate_Bps – Bit rate in Bps.

Returns

kStatus_Success - Set CAN baud rate (only Nominal phase) successfully.

void FLEXCAN_SetFDTimingConfig(CAN_Type *base, const *flexcan_timing_config_t* *pConfig)

Sets the FlexCAN CANFD data phase timing characteristic.

This function gives user settings to CANFD data phase timing characteristic. The function is for an experienced user. For less experienced users, call the *FLEXCAN_SetFDBitRate()* to set both Nominal/Data bit Rate instead.

Note: Calling *FLEXCAN_SetFDTimingConfig()* overrides the data phase bit rate set in *FLEXCAN_FDInit()*/FLEXCAN_SetFDBitRate().

Parameters

- base – FlexCAN peripheral base address.
- pConfig – Pointer to the timing configuration structure.

status_t FLEXCAN_SetFDBitRate(CAN_Type *base, uint32_t sourceClock_Hz, uint32_t bitRateN_Bps, uint32_t bitRateD_Bps)

Set bit rate of FlexCAN FD frame.

This function set the baud rate of FLEXCAN FD base on *FLEXCAN_FDCalculateImprovedTimingValues()* API calculated timing values.

Parameters

- base – FlexCAN peripheral base address.
- sourceClock_Hz – Source Clock in Hz.
- bitRateN_Bps – Nominal bit Rate in Bps.
- bitRateD_Bps – Data bit Rate in Bps.

Returns

kStatus_Success - Set CAN FD bit rate (include Nominal and Data phase) successfully.

void FLEXCAN_SetRxMbGlobalMask(CAN_Type *base, uint32_t mask)

Sets the FlexCAN receive message buffer global mask.

This function sets the global mask for the FlexCAN message buffer in a matching process. The configuration is only effective when the Rx individual mask is disabled in the *FLEXCAN_Init()*.

Parameters

- base – FlexCAN peripheral base address.
- mask – Rx Message Buffer Global Mask value.

void FLEXCAN_SetRxFifoGlobalMask(CAN_Type *base, uint32_t mask)

Sets the FlexCAN receive FIFO global mask.

This function sets the global mask for FlexCAN FIFO in a matching process.

Parameters

- base – FlexCAN peripheral base address.
- mask – Rx Fifo Global Mask value.

void FLEXCAN_SetRxIndividualMask(CAN_Type *base, uint8_t maskIdx, uint32_t mask)

Sets the FlexCAN receive individual mask.

This function sets the individual mask for the FlexCAN matching process. The configuration is only effective when the Rx individual mask is enabled in the *FLEXCAN_Init()*. If the Rx

FIFO is disabled, the individual mask is applied to the corresponding Message Buffer. If the Rx FIFO is enabled, the individual mask for Rx FIFO occupied Message Buffer is applied to the Rx Filter with the same index. Note that only the first 32 individual masks can be used as the Rx FIFO filter mask.

Parameters

- base – FlexCAN peripheral base address.
- maskIdx – The Index of individual Mask.
- mask – Rx Individual Mask value.

void FLEXCAN_SetTxMbConfig(CAN_Type *base, uint8_t mbIdx, bool enable)

Configures a FlexCAN transmit message buffer.

This function aborts the previous transmission, cleans the Message Buffer, and configures it as a Transmit Message Buffer.

Parameters

- base – FlexCAN peripheral base address.
- mbIdx – The Message Buffer index.
- enable – Enable/disable Tx Message Buffer.
  - true: Enable Tx Message Buffer.
  - false: Disable Tx Message Buffer.

void FLEXCAN_SetRxMbConfig(CAN_Type *base, uint8_t mbIdx, const *flexcan_rx_mb_config_t* *pRxMbConfig, bool enable)

Configures a FlexCAN Receive Message Buffer.

This function cleans a FlexCAN build-in Message Buffer and configures it as a Receive Message Buffer. User should invoke this API when CTRL2[RRS]=1. When CTRL2[RRS]=1, frame's ID is compared to the IDs of the receive mailboxes with the CODE field configured as kFLEXCAN_RxMbEmpty, kFLEXCAN_RxMbFull or kFLEXCAN_RxMbOverrun. Message buffer will store the remote frame in the same fashion of a data frame. No automatic remote response frame will be generated. User need to setup another message buffer to respond remote request.

Parameters

- base – FlexCAN peripheral base address.
- mbIdx – The Message Buffer index.
- pRxMbConfig – Pointer to the FlexCAN Message Buffer configuration structure.
- enable – Enable/disable Rx Message Buffer.
  - true: Enable Rx Message Buffer.
  - false: Disable Rx Message Buffer.

static inline void FLEXCAN_SetMbID(CAN_Type *base, uint8_t mbIdx, uint32_t id)

Configures a FlexCAN Message Buffer identifier.

Parameters

- base – FlexCAN peripheral base address.
- mbIdx – The Message Buffer index.
- id – CAN Message Buffer Identifier, should use *FLEXCAN_ID_EXT()* or *FLEXCAN_ID_STD()* macro.

void FLEXCAN_SetFDTxMbConfig(CAN_Type *base, uint8_t mbIdx, bool enable)

Configures a FlexCAN transmit message buffer.

This function aborts the previous transmission, cleans the Message Buffer, and configures it as a Transmit Message Buffer.

Parameters

- base – FlexCAN peripheral base address.
- mbIdx – The Message Buffer index.
- enable – Enable/disable Tx Message Buffer.
  - true: Enable Tx Message Buffer.
  - false: Disable Tx Message Buffer.

void FLEXCAN_SetFDRxMbConfig(CAN_Type *base, uint8_t mbIdx, const *flexcan_rx_mb_config_t* *pRxMbConfig, bool enable)

Configures a FlexCAN Receive Message Buffer.

This function cleans a FlexCAN build-in Message Buffer and configures it as a Receive Message Buffer.

Parameters

- base – FlexCAN peripheral base address.
- mbIdx – The Message Buffer index.
- pRxMbConfig – Pointer to the FlexCAN Message Buffer configuration structure.
- enable – Enable/disable Rx Message Buffer.
  - true: Enable Rx Message Buffer.
  - false: Disable Rx Message Buffer.

static inline void FLEXCAN_SetFDMbID(CAN_Type *base, uint8_t mbIdx, uint32_t id)

Configures a FlexCAN Message Buffer identifier.

Parameters

- base – FlexCAN peripheral base address.
- mbIdx – The Message Buffer index.
- id – CAN Message Buffer Identifier, should use *FLEXCAN_ID_EXT()* or *FLEXCAN_ID_STD()* macro.

void FLEXCAN_SetRemoteResponseMbConfig(CAN_Type *base, uint8_t mbIdx, const *flexcan_frame_t* *pFrame)

Configures a FlexCAN Remote Response Message Buffer.

User should invoke this API when CTRL2[RRS]=0. When CTRL2[RRS]=0, frame's ID is compared to the IDs of the receive mailboxes with the CODE field configured as kFLEXCAN_RxMbRanswer. If there is a matching ID, then this mailbox content will be transmitted as response. The received remote request frame is not stored in receive buffer. It is only used to trigger a transmission of a frame in response.

Parameters

- base – FlexCAN peripheral base address.
- mbIdx – The Message Buffer index.
- pFrame – Pointer to CAN message frame structure for response.

void FLEXCAN_SetRxFifoConfig(CAN_Type *base, const *flexcan_rx_fifo_config_t* *pRxFifoConfig, bool enable)

Configures the FlexCAN Legacy Rx FIFO.

This function configures the FlexCAN Rx FIFO with given configuration.

Note: Legacy Rx FIFO only can receive classic CAN message.

Parameters

- base – FlexCAN peripheral base address.
- pRxFifoConfig – Pointer to the FlexCAN Legacy Rx FIFO configuration structure. Can be NULL when enable parameter is false.
- enable – Enable/disable Legacy Rx FIFO.
  - true: Enable Legacy Rx FIFO.
  - false: Disable Legacy Rx FIFO.

void FLEXCAN_SetEnhancedRxFifoConfig(CAN_Type *base, const *flexcan_enhanced_rx_fifo_config_t* *pConfig, bool enable)

Configures the FlexCAN Enhanced Rx FIFO.

This function configures the Enhanced Rx FIFO with given configuration.

Note: Enhanced Rx FIFO support receive classic CAN or CAN FD messages, Legacy Rx FIFO and Enhanced Rx FIFO cannot be enabled at the same time.

Parameters

- base – FlexCAN peripheral base address.
- pConfig – Pointer to the FlexCAN Enhanced Rx FIFO configuration structure. Can be NULL when enable parameter is false.
- enable – Enable/disable Enhanced Rx FIFO.
  - true: Enable Enhanced Rx FIFO.
  - false: Disable Enhanced Rx FIFO.

void FLEXCAN_SetPNConfig(CAN_Type *base, const *flexcan_pn_config_t* *pConfig)

Configures the FlexCAN Pretended Networking mode.

This function configures the FlexCAN Pretended Networking mode with given configuration.

Parameters

- base – FlexCAN peripheral base address.
- pConfig – Pointer to the FlexCAN Rx FIFO configuration structure.

static inline uint64_t FLEXCAN_GetStatusFlags(CAN_Type *base)

Gets the FlexCAN module interrupt flags.

This function gets all FlexCAN status flags. The flags are returned as the logical OR value of the enumerators *_flexcan_flags*. To check the specific status, compare the return value with enumerators in *_flexcan_flags*.

Parameters

- base – FlexCAN peripheral base address.

Returns
FlexCAN status flags which are ORed by the enumerators in the _flexcan_flags.

static inline void FLEXCAN_ClearStatusFlags(CAN_Type *base, uint64_t mask)

Clears status flags with the provided mask.

This function clears the FlexCAN status flags with a provided mask. An automatically cleared flag can't be cleared by this function.

Parameters

- base – FlexCAN peripheral base address.
- mask – The status flags to be cleared, it is logical OR value of *_flexcan_flags*.

static inline void FLEXCAN_GetBusErrCount(CAN_Type *base, uint8_t *txErrBuf, uint8_t *rxErrBuf)

Gets the FlexCAN Bus Error Counter value.

This function gets the FlexCAN Bus Error Counter value for both Tx and Rx direction. These values may be needed in the upper layer error handling.

Parameters

- base – FlexCAN peripheral base address.
- txErrBuf – Buffer to store Tx Error Counter value.
- rxErrBuf – Buffer to store Rx Error Counter value.

static inline uint64_t FLEXCAN_GetMbStatusFlags(CAN_Type *base, uint64_t mask)

Gets the FlexCAN low 64 Message Buffer interrupt flags.

This function gets the interrupt flags of a given Message Buffers.

Parameters

- base – FlexCAN peripheral base address.
- mask – The ORed FlexCAN Message Buffer mask.

Returns
The status of given Message Buffers.

static inline uint64_t FLEXCAN_GetHigh64MbStatusFlags(CAN_Type *base, uint64_t mask)

Gets the FlexCAN High 64 Message Buffer interrupt flags.

Valid only if the number of available MBs exceeds 64.

Parameters

- base – FlexCAN peripheral base address.
- mask – The ORed FlexCAN Message Buffer mask.

Returns
The status of given Message Buffers.

static inline void FLEXCAN_ClearMbStatusFlags(CAN_Type *base, uint64_t mask)

Clears the FlexCAN low 64 Message Buffer interrupt flags.

This function clears the interrupt flags of a given Message Buffers.

Parameters

- base – FlexCAN peripheral base address.
- mask – The ORed FlexCAN Message Buffer mask.

static inline void FLEXCAN_ClearHigh64MbStatusFlags(CAN_Type *base, uint64_t mask)

Clears the FlexCAN High 64 Message Buffer interrupt flags.

Valid only if the number of available MBs exceeds 64.

Parameters

- base – FlexCAN peripheral base address.
- mask – The ORed FlexCAN Message Buffer mask.

void FLEXCAN_GetMemoryErrorReportStatus(CAN_Type *base, *flexcan_memory_error_report_status_t* *errorStatus)

Gets the FlexCAN Memory Error Report registers status.

This function gets the FlexCAN Memory Error Report registers status.

Parameters

- base – FlexCAN peripheral base address.
- errorStatus – Pointer to FlexCAN Memory Error Report registers status structure.

static inline uint8_t FLEXCAN_GetPNMatchCount(CAN_Type *base)

Gets the FlexCAN Number of Matches when in Pretended Networking.

This function gets the number of times a given message has matched the predefined filtering criteria for ID and/or PL before a wakeup event.

Parameters

- base – FlexCAN peripheral base address.

Returns

The number of received wake up msessages.

static inline uint32_t FLEXCAN_GetEnhancedFifoDataCount(CAN_Type *base)

Gets the number of FlexCAN Enhanced Rx FIFO available frames.

This function gets the number of CAN messages stored in the Enhanced Rx FIFO.

Parameters

- base – FlexCAN peripheral base address.

Returns

The number of available CAN messages stored in the Enhanced Rx FIFO.

static inline void FLEXCAN_EnableInterrupts(CAN_Type *base, uint64_t mask)

Enables FlexCAN interrupts according to the provided mask.

This function enables the FlexCAN interrupts according to the provided mask. The mask is a logical OR of enumeration members, see *_flexcan_interrupt_enable*.

Parameters

- base – FlexCAN peripheral base address.
- mask – The interrupts to enable. Logical OR of *_flexcan_interrupt_enable*.

static inline void FLEXCAN_DisableInterrupts(CAN_Type *base, uint64_t mask)

Disables FlexCAN interrupts according to the provided mask.

This function disables the FlexCAN interrupts according to the provided mask. The mask is a logical OR of enumeration members, see *_flexcan_interrupt_enable*.

Parameters

- base – FlexCAN peripheral base address.

- mask – The interrupts to disable. Logical OR of *_flexcan_interrupt_enable*.

static inline void FLEXCAN_EnableMbInterrupts(CAN_Type *base, uint64_t mask)

Enables FlexCAN low 64 Message Buffer interrupts.

This function enables the interrupts of given Message Buffers.

Parameters

- base – FlexCAN peripheral base address.
- mask – The ORed FlexCAN Message Buffer mask.

static inline void FLEXCAN_EnableHigh64MbInterrupts(CAN_Type *base, uint64_t mask)

Enables FlexCAN high 64 Message Buffer interrupts.

Valid only if the number of available MBs exceeds 64.

Parameters

- base – FlexCAN peripheral base address.
- mask – The ORed FlexCAN Message Buffer mask.

static inline void FLEXCAN_DisableMbInterrupts(CAN_Type *base, uint64_t mask)

Disables FlexCAN low 64 Message Buffer interrupts.

This function disables the interrupts of given Message Buffers.

Parameters

- base – FlexCAN peripheral base address.
- mask – The ORed FlexCAN Message Buffer mask.

static inline void FLEXCAN_DisableHigh64MbInterrupts(CAN_Type *base, uint64_t mask)

Disables FlexCAN high 64 Message Buffer interrupts.

Valid only if the number of available MBs exceeds 64.

Parameters

- base – FlexCAN peripheral base address.
- mask – The ORed FlexCAN Message Buffer mask.

void FLEXCAN_EnableRxFifoDMA(CAN_Type *base, bool enable)

Enables or disables the FlexCAN Rx FIFO DMA request.

This function enables or disables the DMA feature of FlexCAN build-in Rx FIFO.

Parameters

- base – FlexCAN peripheral base address.
- enable – true to enable, false to disable.

static inline uintptr_t FLEXCAN_GetRxFifoHeadAddr(CAN_Type *base)

Gets the Rx FIFO Head address.

This function returns the FlexCAN Rx FIFO Head address, which is mainly used for the DMA/eDMA use case.

Parameters

- base – FlexCAN peripheral base address.

Returns

FlexCAN Rx FIFO Head address.

static inline *status_t* FLEXCAN_Enable(CAN_Type *base, bool enable)

Enables or disables the FlexCAN module operation.

This function enables or disables the FlexCAN module.

Parameters

- base – FlexCAN base pointer.
- enable – true to enable, false to disable.

Returns

kStatus_Success Enable FlexCAN module successful kStatus_Timeout Timeout when wait for Low-Power Mode Acknowledge

status_t FLEXCAN_WriteTxMb(CAN_Type *base, uint8_t mbIdx, const *flexcan_frame_t* *pTxFrame)

Writes a FlexCAN Message to the Transmit Message Buffer.

This function writes a CAN Message to the specified Transmit Message Buffer and changes the Message Buffer state to start CAN Message transmit. After that the function returns immediately.

Parameters

- base – FlexCAN peripheral base address.
- mbIdx – The FlexCAN Message Buffer index.
- pTxFrame – Pointer to CAN message frame to be sent.

Return values

- kStatus_Success – - Write Tx Message Buffer Successfully.
- kStatus_Fail – - Tx Message Buffer is currently in use.

status_t FLEXCAN_ReadRxMb(CAN_Type *base, uint8_t mbIdx, *flexcan_frame_t* *pRxFrame)

Reads a FlexCAN Message from Receive Message Buffer.

This function reads a CAN message from a specified Receive Message Buffer. The function fills a receive CAN message frame structure with just received data and activates the Message Buffer again. The function returns immediately.

Parameters

- base – FlexCAN peripheral base address.
- mbIdx – The FlexCAN Message Buffer index.
- pRxFrame – Pointer to CAN message frame structure for reception.

Return values

- kStatus_Success – - Rx Message Buffer is full and has been read successfully.
- kStatus_FLEXCAN_RxOverflow – - Rx Message Buffer is already overflowed and has been read successfully.
- kStatus_Fail – - Rx Message Buffer is empty or inactive.
- kStatus_Timeout – - Timeout when wait for Rx Message Buffer busy.

status_t FLEXCAN_WriteFDTxMb(CAN_Type *base, uint8_t mbIdx, const *flexcan_fd_frame_t* *pTxFrame)

Writes a FlexCAN FD Message to the Transmit Message Buffer.

This function writes a CAN FD Message to the specified Transmit Message Buffer and changes the Message Buffer state to start CAN FD Message transmit. After that the function returns immediately.

Parameters

- base – FlexCAN peripheral base address.
- mbIdx – The FlexCAN FD Message Buffer index.
- pTxFrame – Pointer to CAN FD message frame to be sent.

Return values

- kStatus_Success – - Write Tx Message Buffer Successfully.
- kStatus_Fail – - Tx Message Buffer is currently in use.

status_t FLEXCAN_ReadFDRxMb(CAN_Type *base, uint8_t mbIdx, *flexcan_fd_frame_t* *pRxFrame)

Reads a FlexCAN FD Message from Receive Message Buffer.

This function reads a CAN FD message from a specified Receive Message Buffer. The function fills a receive CAN FD message frame structure with just received data and activates the Message Buffer again. The function returns immediately.

Parameters

- base – FlexCAN peripheral base address.
- mbIdx – The FlexCAN FD Message Buffer index.
- pRxFrame – Pointer to CAN FD message frame structure for reception.

Return values

- kStatus_Success – - Rx Message Buffer is full and has been read successfully.
- kStatus_FLEXCAN_RxOverflow – - Rx Message Buffer is already overflowed and has been read successfully.
- kStatus_Fail – - Rx Message Buffer is empty or inactive.
- kStatus_Timeout – - Timeout when wait for Rx Message Buffer busy.

status_t FLEXCAN_ReadRxFifo(CAN_Type *base, *flexcan_frame_t* *pRxFrame)

Reads a FlexCAN Message from Legacy Rx FIFO.

This function reads a CAN message from the FlexCAN Legacy Rx FIFO.

Parameters

- base – FlexCAN peripheral base address.
- pRxFrame – Pointer to CAN message frame structure for reception.

Return values

- kStatus_Success – - Read Message from Rx FIFO successfully.
- kStatus_Fail – - Rx FIFO is not enabled.

status_t FLEXCAN_ReadEnhancedRxFifo(CAN_Type *base, *flexcan_fd_frame_t* *pRxFrame)

Reads a FlexCAN Message from Enhanced Rx FIFO.

This function reads a CAN or CAN FD message from the FlexCAN Enhanced Rx FIFO.

Parameters

- base – FlexCAN peripheral base address.
- pRxFrame – Pointer to CAN FD message frame structure for reception.

Return values

- kStatus_Success – - Read Message from Rx FIFO successfully.
- kStatus_Fail – - Rx FIFO is not enabled.

status_t FLEXCAN_ReadPNWakeUpMB(CAN_Type *base, uint8_t mbIdx, *flexcan_frame_t* *pRxFrame)

Reads a FlexCAN Message from Wake Up MB.

This function reads a CAN message from the FlexCAN Wake up Message Buffers. There are four Wake up Message Buffers (WMBs) used to store incoming messages in Pretended Networking mode. The WMB index indicates the arrival order. The last message is stored in WMB3.

Parameters

- base – FlexCAN peripheral base address.
- pRxFrame – Pointer to CAN message frame structure for reception.
- mbIdx – The FlexCAN Wake up Message Buffer index. Range in 0x0 ~ 0x3.

Return values

- kStatus_Success – - Read Message from Wake up Message Buffer successfully.
- kStatus_Fail – - Wake up Message Buffer has no valid content.

status_t FLEXCAN_TransferFDSendBlocking(CAN_Type *base, uint8_t mbIdx, *flexcan_fd_frame_t* *pTxFrame)

Performs a polling send transaction on the CAN bus.

Note: A transfer handle does not need to be created before calling this API.

Parameters

- base – FlexCAN peripheral base pointer.
- mbIdx – The FlexCAN FD Message Buffer index.
- pTxFrame – Pointer to CAN FD message frame to be sent.

Return values

- kStatus_Success – - Write Tx Message Buffer Successfully.
- kStatus_Fail – - Tx Message Buffer is currently in use.
- kStatus_Timeout – - Failed to send frames within specific time.

status_t FLEXCAN_TransferFDReceiveBlocking(CAN_Type *base, uint8_t mbIdx, *flexcan_fd_frame_t* *pRxFrame)

Performs a polling receive transaction on the CAN bus.

Note: A transfer handle does not need to be created before calling this API.

Parameters

- base – FlexCAN peripheral base pointer.
- mbIdx – The FlexCAN FD Message Buffer index.
- pRxFrame – Pointer to CAN FD message frame structure for reception.

Return values

- kStatus_Success – - Rx Message Buffer is full and has been read successfully.

- kStatus_FLEXCAN_RxOverflow – - Rx Message Buffer is already overflowed and has been read successfully.
- kStatus_Fail – - Rx Message Buffer is empty.
- kStatus_Timeout – - Failed to receive frames within specific time.

status_t FLEXCAN_TransferFDSendNonBlocking(CAN_Type *base, *flexcan_handle_t* *handle, *flexcan_mb_transfer_t* *pMbXfer)

Sends a message using IRQ.

This function sends a message using IRQ. This is a non-blocking function, which returns right away. When messages have been sent out, the send callback function is called.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.
- pMbXfer – FlexCAN FD Message Buffer transfer structure. See the *flexcan_mb_transfer_t*.

Return values

- kStatus_Success – Start Tx Message Buffer sending process successfully.
- kStatus_Fail – Write Tx Message Buffer failed.
- kStatus_FLEXCAN_TxBusy – Tx Message Buffer is in use.

status_t FLEXCAN_TransferFDReceiveNonBlocking(CAN_Type *base, *flexcan_handle_t* *handle, *flexcan_mb_transfer_t* *pMbXfer)

Receives a message using IRQ.

This function receives a message using IRQ. This is non-blocking function, which returns right away. When the message has been received, the receive callback function is called.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.
- pMbXfer – FlexCAN FD Message Buffer transfer structure. See the *flexcan_mb_transfer_t*.

Return values

- kStatus_Success – - Start Rx Message Buffer receiving process successfully.
- kStatus_FLEXCAN_RxBusy – - Rx Message Buffer is in use.

void FLEXCAN_TransferFDAbortSend(CAN_Type *base, *flexcan_handle_t* *handle, uint8_t mbIdx)

Aborts the interrupt driven message send process.

This function aborts the interrupt driven message send process.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.
- mbIdx – The FlexCAN FD Message Buffer index.

void FLEXCAN_TransferFDAbortReceive(CAN_Type *base, *flexcan_handle_t* *handle, uint8_t mbIdx)

Aborts the interrupt driven message receive process.

This function aborts the interrupt driven message receive process.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.
- mbIdx – The FlexCAN FD Message Buffer index.

status_t FLEXCAN_TransferSendBlocking(CAN_Type *base, uint8_t mbIdx, *flexcan_frame_t* *pTxFrame)

Performs a polling send transaction on the CAN bus.

Note: A transfer handle does not need to be created before calling this API.

Parameters

- base – FlexCAN peripheral base pointer.
- mbIdx – The FlexCAN Message Buffer index.
- pTxFrame – Pointer to CAN message frame to be sent.

Return values

- kStatus_Success – - Write Tx Message Buffer Successfully.
- kStatus_Fail – - Tx Message Buffer is currently in use.
- kStatus_Timeout – - Failed to send frames within specific time.

status_t FLEXCAN_TransferReceiveBlocking(CAN_Type *base, uint8_t mbIdx, *flexcan_frame_t* *pRxFrame)

Performs a polling receive transaction on the CAN bus.

Note: A transfer handle does not need to be created before calling this API.

Parameters

- base – FlexCAN peripheral base pointer.
- mbIdx – The FlexCAN Message Buffer index.
- pRxFrame – Pointer to CAN message frame structure for reception.

Return values

- kStatus_Success – - Rx Message Buffer is full and has been read successfully.
- kStatus_FLEXCAN_RxOverflow – - Rx Message Buffer is already overflowed and has been read successfully.
- kStatus_Fail – - Rx Message Buffer is empty.
- kStatus_Timeout – - Failed to receive frames within specific time.

status_t FLEXCAN_TransferReceiveFifoBlocking(CAN_Type *base, *flexcan_frame_t* *pRxFrame)

Performs a polling receive transaction from Legacy Rx FIFO on the CAN bus.

Note: A transfer handle does not need to be created before calling this API.

Parameters

- base – FlexCAN peripheral base pointer.
- pRxFrame – Pointer to CAN message frame structure for reception.

Return values

- kStatus_Success – - Read Message from Rx FIFO successfully.
- kStatus_Fail – - Rx FIFO is not enabled.
- kStatus_Timeout – - Failed to receive frames within specific time.

status_t FLEXCAN_TransferReceiveEnhancedFifoBlocking(CAN_Type *base, *flexcan_fd_frame_t* *pRxFrame)

Performs a polling receive transaction from Enhanced Rx FIFO on the CAN bus.

Note: A transfer handle does not need to be created before calling this API.

Parameters

- base – FlexCAN peripheral base pointer.
- pRxFrame – Pointer to CAN FD message frame structure for reception.

Return values

- kStatus_Success – - Read Message from Rx FIFO successfully.
- kStatus_Fail – - Rx FIFO is not enabled.
- kStatus_Timeout – - Failed to receive frames within specific time.

void FLEXCAN_TransferCreateHandle(CAN_Type *base, *flexcan_handle_t* *handle, *flexcan_transfer_callback_t* callback, void *userData)

Initializes the FlexCAN handle.

This function initializes the FlexCAN handle, which can be used for other FlexCAN transactional APIs. Usually, for a specified FlexCAN instance, call this API once to get the initialized handle.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.
- callback – The callback function.
- userData – The parameter of the callback function.

status_t FLEXCAN_TransferSendNonBlocking(CAN_Type *base, *flexcan_handle_t* *handle, *flexcan_mb_transfer_t* *pMbXfer)

Sends a message using IRQ.

This function sends a message using IRQ. This is a non-blocking function, which returns right away. When messages have been sent out, the send callback function is called.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.
- pMbXfer – FlexCAN Message Buffer transfer structure. See the *flexcan_mb_transfer_t*.

Return values

- kStatus_Success – Start Tx Message Buffer sending process successfully.
- kStatus_Fail – Write Tx Message Buffer failed.
- kStatus_FLEXCAN_TxBusy – Tx Message Buffer is in use.

status_t FLEXCAN_TransferReceiveNonBlocking(CAN_Type *base, *flexcan_handle_t* *handle, *flexcan_mb_transfer_t* *pMbXfer)

Receives a message using IRQ.

This function receives a message using IRQ. This is non-blocking function, which returns right away. When the message has been received, the receive callback function is called.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.
- pMbXfer – FlexCAN Message Buffer transfer structure. See the *flexcan_mb_transfer_t*.

Return values

- kStatus_Success – - Start Rx Message Buffer receiving process successfully.
- kStatus_FLEXCAN_RxBusy – - Rx Message Buffer is in use.

status_t FLEXCAN_TransferRemoteRequestNonBlocking(CAN_Type *base, *flexcan_handle_t* *handle, *flexcan_mb_transfer_t* *pMbXfer)

Sends a remote request frame using IRQ.

This function sends a remote request frame using IRQ. This is a non-blocking function, which returns right away. When the remote request frame has been sent out, the send callback function is called. User should invoke API FLEXCAN_TransferReceiveNonBlocking to receive the response frame. Receive message buffer index should less than send message buffer index.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.
- pMbXfer – FlexCAN Message Buffer transfer structure. See the *flexcan_mb_transfer_t*.

Return values

- kStatus_Success – Start Tx remote request frame sending process successfully.
- kStatus_Fail – Write Tx Message Buffer failed.
- kStatus_FLEXCAN_TxBusy – Message Buffer is transmitting remote request frame.

status_t FLEXCAN_TransferRemoteResponseNonBlocking(CAN_Type *base, *flexcan_handle_t* *handle, *flexcan_mb_transfer_t* *pMbXfer)

Configures a FlexCAN Message Buffer for automatic remote response using IRQ.

This function configures a Message Buffer to automatically respond to remote request frames using IRQ. This is a non-blocking function, which returns right away. When a matching remote request frame is received, the configured response frame will be transmitted automatically, and the callback function will be called. User should invoke this API when CTRL2[RRS]=0. When CTRL2[RRS]=0, if a remote request frame is received and matches a mailbox configured with CODE=kFLEXCAN_RxMbRanswer, the mailbox content will be transmitted as a response frame automatically. The received remote request frame is not stored.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.
- pMbXfer – FlexCAN Message Buffer transfer structure. See the *flexcan_mb_transfer_t*.

Return values

- kStatus_Success – Configure remote response Message Buffer successfully.
- kStatus_Busy – Message Buffer is waiting for remote request frame or transmitting response frame.

status_t FLEXCAN_TransferReceiveFifoNonBlocking(CAN_Type *base, *flexcan_handle_t* *handle, *flexcan_fifo_transfer_t* *pFifoXfer)

Receives a message from Rx FIFO using IRQ.

This function receives a message using IRQ. This is a non-blocking function, which returns right away. When all messages have been received, the receive callback function is called.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.
- pFifoXfer – FlexCAN Rx FIFO transfer structure. See the *flexcan_fifo_transfer_t*.

Return values

- kStatus_Success – - Start Rx FIFO receiving process successfully.
- kStatus_FLEXCAN_RxFifoBusy – - Rx FIFO is currently in use.

status_t FLEXCAN_TransferGetReceiveFifoCount(CAN_Type *base, *flexcan_handle_t* *handle, size_t *count)

Gets the Rx Fifo transfer status during a interrupt non-blocking receive.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.
- count – Number of CAN messages receive so far by the non-blocking transaction.

Return values

- kStatus_InvalidArgument – count is Invalid.
- kStatus_Success – Successfully return the count.

status_t FLEXCAN_TransferReceiveEnhancedFifoNonBlocking(CAN_Type *base, *flexcan_handle_t* *handle, *flexcan_fifo_transfer_t* *pFifoXfer)

Receives a message from Enhanced Rx FIFO using IRQ.

This function receives a message using IRQ. This is a non-blocking function, which returns right away. When all messages have been received, the receive callback function is called.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.
- pFifoXfer – FlexCAN Rx FIFO transfer structure. See the ref flexcan_fifo_transfer_t.@

Return values

- kStatus_Success – - Start Rx FIFO receiving process successfully.
- kStatus_FLEXCAN_RxFifoBusy – - Rx FIFO is currently in use.

static inline *status_t* FLEXCAN_TransferGetReceiveEnhancedFifoCount(CAN_Type *base, *flexcan_handle_t* *handle, size_t *count)

Gets the Enhanced Rx Fifo transfer status during a interrupt non-blocking receive.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.
- count – Number of CAN messages receive so far by the non-blocking transaction.

Return values

- kStatus_InvalidArgument – count is Invalid.
- kStatus_Success – Successfully return the count.

uint32_t FLEXCAN_GetTimeStamp(*flexcan_handle_t* *handle, uint8_t mbIdx)

Gets the detail index of Mailbox's Timestamp by handle.

Then function can only be used when calling non-blocking Data transfer (TX/RX) API, After TX/RX data transfer done (User can get the status by handler's callback function), we can get the detail index of Mailbox's timestamp by handle, Detail non-blocking data transfer API (TX/RX) contain. -FLEXCAN_TransferSendNonBlocking -FLEXCAN_TransferFDSendNonBlocking -FLEXCAN_TransferReceiveNonBlocking -FLEXCAN_TransferFDReceiveNonBlocking -FLEXCAN_TransferReceiveFifoNonBlocking

Parameters

- handle – FlexCAN handle pointer.
- mbIdx – The FlexCAN Message Buffer index.

Return values

the – index of mailbox 's timestamp stored in the handle.

static inline uint32_t FLEXCAN_GetHighResolutionTimeStamp(CAN_Type *base, uint8_t mbIdx)

void FLEXCAN_TransferAbortSend(CAN_Type *base, *flexcan_handle_t* *handle, uint8_t mbIdx)

Aborts the interrupt driven message send process.

This function aborts the interrupt driven message send process.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.
- mbIdx – The FlexCAN Message Buffer index.

void FLEXCAN_TransferAbortReceive(CAN_Type *base, *flexcan_handle_t* *handle, uint8_t mbIdx)

Aborts the interrupt driven message receive process.

This function aborts the interrupt driven message receive process.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.
- mbIdx – The FlexCAN Message Buffer index.

void FLEXCAN_TransferAbortReceiveFifo(CAN_Type *base, *flexcan_handle_t* *handle)

Aborts the interrupt driven message receive from Rx FIFO process.

This function aborts the interrupt driven message receive from Rx FIFO process.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.

void FLEXCAN_TransferAbortReceiveEnhancedFifo(CAN_Type *base, *flexcan_handle_t* *handle)

Aborts the interrupt driven message receive from Enhanced Rx FIFO process.

This function aborts the interrupt driven message receive from Enhanced Rx FIFO process.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.

void FLEXCAN_TransferHandleIRQ(CAN_Type *base, *flexcan_handle_t* *handle)

FlexCAN IRQ handle function.

This function handles the FlexCAN Error, the Message Buffer, and the Rx FIFO IRQ request.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.

void FLEXCAN_MbHandleIRQ(CAN_Type *base, *flexcan_handle_t* *handle, uint32_t startMbIdx, uint32_t endMbIdx)

FlexCAN Message Buffer IRQ handle function.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.
- startMbIdx – First Message Buffer to handle.
- endMbIdx – Last Message Buffer to handle.

void FLEXCAN_EnhancedRxFifoHandleIRQ(CAN_Type *base, *flexcan_handle_t* *handle)

FlexCAN Enhanced Rx FIFO IRQ handle function.

Parameters

- base – FlexCAN peripheral base address.

- handle – FlexCAN handle pointer.

void FLEXCAN_BusoffErrorHandleIRQ(CAN_Type *base, *flexcan_handle_t* *handle)

FlexCAN Bus Off, Error and Warning IRQ handle function.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.

void FLEXCAN_PNWakeUpHandleIRQ(CAN_Type *base, *flexcan_handle_t* *handle)

FlexCAN Pretended Networking Wake-up IRQ handle function.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.

void FLEXCAN_MemoryErrorHandleIRQ(CAN_Type *base, *flexcan_handle_t* *handle)

FlexCAN Memory Error IRQ handle function.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.

FSL_FLEXCAN_DRIVER_VERSION

FlexCAN driver version.

FlexCAN transfer status.

Values:

enumerator kStatus_FLEXCAN_TxBusy

Tx Message Buffer is Busy.

enumerator kStatus_FLEXCAN_TxIdle

Tx Message Buffer is Idle.

enumerator kStatus_FLEXCAN_TxSwitchToRx

Remote Message is send out and Message buffer changed to Receive one.

enumerator kStatus_FLEXCAN_RxBusy

Rx Message Buffer is Busy.

enumerator kStatus_FLEXCAN_RxIdle

Rx Message Buffer is Idle.

enumerator kStatus_FLEXCAN_RxOverflow

Rx Message Buffer is Overflowed.

enumerator kStatus_FLEXCAN_RxFifoBusy

Rx Message FIFO is Busy.

enumerator kStatus_FLEXCAN_RxFifoIdle
Rx Message FIFO is Idle.

enumerator kStatus_FLEXCAN_RxFifoOverflow
Rx Message FIFO is overflowed.

enumerator kStatus_FLEXCAN_RxFifoWarning
Rx Message FIFO is almost overflowed.

enumerator kStatus_FLEXCAN_RxFifoDisabled
Rx Message FIFO is disabled during reading.

enumerator kStatus_FLEXCAN_ErrorStatus
FlexCAN Module Error and Status.

enumerator kStatus_FLEXCAN_WakeUp
FlexCAN is waken up from STOP mode.

enumerator kStatus_FLEXCAN_UnHandled
UnHadled Interrupt asserted.

enumerator kStatus_FLEXCAN_RxRemote
Rx Remote Message Received in Mail box.

enumerator kStatus_FLEXCAN_RxFifoUnderflow
Enhanced Rx Message FIFO is underflow.

enumerator kStatus_FLEXCAN_MemoryError
FlexCAN Memory Error.

enum _flexcan_frame_format
FlexCAN frame format.
Values:

enumerator kFLEXCAN_FrameFormatStandard
Standard frame format attribute.

enumerator kFLEXCAN_FrameFormatExtend
Extend frame format attribute.

enum _flexcan_frame_type
FlexCAN frame type.
Values:

enumerator kFLEXCAN_FrameTypeData
Data frame type attribute.

enumerator kFLEXCAN_FrameTypeRemote
Remote frame type attribute.

enum _flexcan_clock_source
FlexCAN clock source.

Deprecated:
Do not use the kFLEXCAN_ClkSrcOs. It has been superceded kFLEXCAN_ClkSrc0
Do not use the kFLEXCAN_ClkSrcPeri. It has been superceded kFLEXCAN_ClkSrc1
Values:

enumerator kFLEXCAN_ClkSrcOsc
FlexCAN Protocol Engine clock from Oscillator.

enumerator kFLEXCAN_ClkSrcPeri
FlexCAN Protocol Engine clock from Peripheral Clock.

enumerator kFLEXCAN_ClkSrc0
FlexCAN Protocol Engine clock selected by user as SRC == 0.

enumerator kFLEXCAN_ClkSrc1
FlexCAN Protocol Engine clock selected by user as SRC == 1.

enum _flexcan_wake_up_source
FlexCAN wake up source.
Values:

enumerator kFLEXCAN_WakeupSrcUnfiltered
FlexCAN uses unfiltered Rx input to detect edge.

enumerator kFLEXCAN_WakeupSrcFiltered
FlexCAN uses filtered Rx input to detect edge.

enum _flexcan_endianness
FlexCAN payload endianness.
Values:

enumerator kFLEXCAN_bigEndian
Transmit frame with MSB first, receive frame with big-endian format.

enumerator kFLEXCAN_littleEndian
Transmit frame with LSB first, receive frame with little-endian format.

enum _flexcan_MB_timestamp_base
FlexCAN timebase used for capturing 16-bit TIME_STAMP field of message buffer.
Values:

enumerator kFLEXCAN_CANTimer
FlexCAN free-running timer.

enumerator kFLEXCAN_Lower16bitsHRTimer
Lower 16 bits of high-resolution on-chip timer.

enumerator kFLEXCAN_Upper16bitsHRTimer
Upper 16 bits of high-resolution on-chip timer.

enum _flexcan_capture_point
FlexCAN capture point of 32-bit high resolution timebase during a CAN frame.
Values:

enumerator kFLEXCAN_CANFrameID2ndBit
Second bit of identifier field of any frame is on the CAN bus. HR_TIME_STAMPn register will not capture 32-bit counter value.

enumerator kFLEXCAN_CANFrameEnd
End of the CAN frame.

enumerator kFLEXCAN_CANFrameStart
Start of the CAN frame.

enumerator kFLEXCAN_CANFDFrameRes
Start of frame for classical CAN frames; res bit for CAN FD frames.

enum _flexcan_rx_fifo_filter_type
FlexCAN Rx Fifo Filter type.
Values:

enumerator kFLEXCAN_RxFifoFilterTypeA
One full ID (standard and extended) per ID Filter element.

enumerator kFLEXCAN_RxFifoFilterTypeB
Two full standard IDs or two partial 14-bit ID slices per ID Filter Table element.

enumerator kFLEXCAN_RxFifoFilterTypeC
Four partial 8-bit Standard or extended ID slices per ID Filter Table element.

enumerator kFLEXCAN_RxFifoFilterTypeD
All frames rejected.

enum _flexcan_mb_size
FlexCAN Message Buffer Payload size.
Values:

enumerator kFLEXCAN_8BperMB
Selects 8 bytes per Message Buffer.

enumerator kFLEXCAN_16BperMB
Selects 16 bytes per Message Buffer.

enumerator kFLEXCAN_32BperMB
Selects 32 bytes per Message Buffer.

enumerator kFLEXCAN_64BperMB
Selects 64 bytes per Message Buffer.

enum _flexcan_fd_frame_length
FlexCAN CAN FD frame supporting data length (available DLC values).

For Tx, when the Data size corresponding to DLC value stored in the MB selected for transmission is larger than the MB Payload size, FlexCAN adds the necessary number of bytes with constant 0xCC pattern to complete the expected DLC. For Rx, when the Data size corresponding to DLC value received from the CAN bus is larger than the MB Payload size, the high order bytes that do not fit the Payload size will lose.

Values:

enumerator kFLEXCAN_0BperFrame
Frame contains 0 valid data bytes.

enumerator kFLEXCAN_1BperFrame
Frame contains 1 valid data bytes.

enumerator kFLEXCAN_2BperFrame
Frame contains 2 valid data bytes.

enumerator kFLEXCAN_3BperFrame
Frame contains 3 valid data bytes.

enumerator kFLEXCAN_4BperFrame
Frame contains 4 valid data bytes.

enumerator kFLEXCAN_5BperFrame
Frame contains 5 valid data bytes.

enumerator kFLEXCAN_6BperFrame
Frame contains 6 valid data bytes.

enumerator kFLEXCAN_7BperFrame
Frame contains 7 valid data bytes.

enumerator kFLEXCAN_8BperFrame
Frame contains 8 valid data bytes.

enumerator kFLEXCAN_12BperFrame
Frame contains 12 valid data bytes.

enumerator kFLEXCAN_16BperFrame
Frame contains 16 valid data bytes.

enumerator kFLEXCAN_20BperFrame
Frame contains 20 valid data bytes.

enumerator kFLEXCAN_24BperFrame
Frame contains 24 valid data bytes.

enumerator kFLEXCAN_32BperFrame
Frame contains 32 valid data bytes.

enumerator kFLEXCAN_48BperFrame
Frame contains 48 valid data bytes.

enumerator kFLEXCAN_64BperFrame
Frame contains 64 valid data bytes.

enum _flexcan_efifo_dma_per_read_length
FlexCAN Enhanced Rx Fifo DMA transfer per read length enumerations.
Values:

enumerator kFLEXCAN_1WordPerRead
Transfer 1 32-bit words (CS).

enumerator kFLEXCAN_2WordPerRead
Transfer 2 32-bit words (CS + ID).

enumerator kFLEXCAN_3WordPerRead
Transfer 3 32-bit words (CS + ID + 1~4 bytes data).

enumerator kFLEXCAN_4WordPerRead
Transfer 4 32-bit words (CS + ID + 5~8 bytes data).

enumerator kFLEXCAN_5WordPerRead
Transfer 5 32-bit words (CS + ID + 9~12 bytes data).

enumerator kFLEXCAN_6WordPerRead
Transfer 6 32-bit words (CS + ID + 13~16 bytes data).

enumerator kFLEXCAN_7WordPerRead
Transfer 7 32-bit words (CS + ID + 17~20 bytes data).

enumerator kFLEXCAN_8WordPerRead
Transfer 8 32-bit words (CS + ID + 21~24 bytes data).

enumerator kFLEXCAN_9WordPerRead
Transfer 9 32-bit words (CS + ID + 25~28 bytes data).

enumerator kFLEXCAN_10WordPerRead
Transfer 10 32-bit words (CS + ID + 29~32 bytes data).

enumerator kFLEXCAN_11WordPerRead
Transfer 11 32-bit words (CS + ID + 33~36 bytes data).

enumerator kFLEXCAN_12WordPerRead
Transfer 12 32-bit words (CS + ID + 37~40 bytes data).

enumerator kFLEXCAN_13WordPerRead
Transfer 13 32-bit words (CS + ID + 41~44 bytes data).

enumerator kFLEXCAN_14WordPerRead
Transfer 14 32-bit words (CS + ID + 45~48 bytes data).

enumerator kFLEXCAN_15WordPerRead
Transfer 15 32-bit words (CS + ID + 49~52 bytes data).

enumerator kFLEXCAN_16WordPerRead
Transfer 16 32-bit words (CS + ID + 53~56 bytes data).

enumerator kFLEXCAN_17WordPerRead
Transfer 17 32-bit words (CS + ID + 57~60 bytes data).

enumerator kFLEXCAN_18WordPerRead
Transfer 18 32-bit words (CS + ID + 61~64 bytes data).

enumerator kFLEXCAN_19WordPerRead
Transfer 19 32-bit words (CS + ID + 64 bytes data + ID HIT).

enumerator kFLEXCAN_20WordPerRead
Transfer 20 32-bit words (CS + ID + 64 bytes data + ID HIT + HR timestamp).

enum _flexcan_rx_fifo_priority
FlexCAN Enhanced/Legacy Rx FIFO priority.

The matching process starts from the Rx MB(or Enhanced/Legacy Rx FIFO) with higher priority. If no MB(or Enhanced/Legacy Rx FIFO filter) is satisfied, the matching process goes on with the Enhanced/Legacy Rx FIFO(or Rx MB) with lower priority.

Values:

enumerator kFLEXCAN_RxFifoPrioLow
Matching process start from Rx Message Buffer first.

enumerator kFLEXCAN_RxFifoPrioHigh
Matching process start from Enhanced/Legacy Rx FIFO first.

enum _flexcan_interrupt_enable

FlexCAN interrupt enable enumerations.

This provides constants for the FlexCAN interrupt enable enumerations for use in the FlexCAN functions.

Note: FlexCAN Message Buffers and Legacy Rx FIFO interrupts not included in.

Values:

enumerator kFLEXCAN_BusOffInterruptEnable
Bus Off interrupt, use bit 15.

enumerator kFLEXCAN_ErrorInterruptEnable
CAN Error interrupt, use bit 14.

enumerator kFLEXCAN_TxWarningInterruptEnable
Tx Warning interrupt, use bit 11.

enumerator kFLEXCAN_RxWarningInterruptEnable
Rx Warning interrupt, use bit 10.

enumerator kFLEXCAN_FDErrorInterruptEnable
CAN FD Error interrupt, use bit 31.

enumerator kFLEXCAN_PNMatchWakeUpInterruptEnable
PN Match Wake Up interrupt, use high word bit 17.

enumerator kFLEXCAN_PNTimeoutWakeUpInterruptEnable
PN Timeout Wake Up interrupt, use high word bit 16. Enhanced Rx FIFO Underflow interrupt, use high word bit 31.

enumerator kFLEXCAN_ERxFifoUnderflowInterruptEnable
Enhanced Rx FIFO Overflow interrupt, use high word bit 30.

enumerator kFLEXCAN_ERxFifoOverflowInterruptEnable
Enhanced Rx FIFO Watermark interrupt, use high word bit 29.

enumerator kFLEXCAN_ERxFifoWatermarkInterruptEnable
Enhanced Rx FIFO Data Avilable interrupt, use high word bit 28.

enumerator kFLEXCAN_ERxFifoDataAvlInterruptEnable

enumerator kFLEXCAN_HostAccessNCErrorInterruptEnable
Host Access With Non-Correctable Errors interrupt, use high word bit 0.

enumerator kFLEXCAN_FlexCanAccessNCErrorInterruptEnable
FlexCAN Access With Non-Correctable Errors interrupt, use high word bit 2.

enumerator kFLEXCAN_HostOrFlexCanCErrorInterruptEnable

Host or FlexCAN Access With Correctable Errors interrupt, use high word bit 3.

enum _flexcan_flags

FlexCAN status flags.

This provides constants for the FlexCAN status flags for use in the FlexCAN functions.

Note: The CPU read action clears the bits corresponding to the FlEXCAN_ErrorFlag macro, therefore user need to read status flags and distinguish which error is occur using *_flexcan_error_flags* enumerations.

Values:

enumerator kFLEXCAN_ErrorOverrunFlag

Error Overrun Status.

enumerator kFLEXCAN_FDErrorIntFlag

CAN FD Error Interrupt Flag.

enumerator kFLEXCAN_BusoffDoneIntFlag

Bus Off process completed Interrupt Flag.

enumerator kFLEXCAN_SynchFlag

CAN Synchronization Status.

enumerator kFLEXCAN_TxWarningIntFlag

Tx Warning Interrupt Flag.

enumerator kFLEXCAN_RxWarningIntFlag

Rx Warning Interrupt Flag.

enumerator kFLEXCAN_IdleFlag

FlexCAN In IDLE Status.

enumerator kFLEXCAN_FaultConfinementFlag

FlexCAN Fault Confinement State.

enumerator kFLEXCAN_TransmittingFlag

FlexCAN In Transmission Status.

enumerator kFLEXCAN_ReceivingFlag

FlexCAN In Reception Status.

enumerator kFLEXCAN_BusOffIntFlag

Bus Off Interrupt Flag.

enumerator kFLEXCAN_ErrorIntFlag

CAN Error Interrupt Flag.

enumerator kFLEXCAN_ErrorFlag

enumerator kFLEXCAN_PNMatchIntFlag
PN Matching Event Interrupt Flag.

enumerator kFLEXCAN_PNTimeoutIntFlag
PN Timeout Event Interrupt Flag.

enumerator kFLEXCAN_ERxFifoUnderflowIntFlag
Enhanced Rx FIFO underflow Interrupt Flag.

enumerator kFLEXCAN_ERxFifoOverflowIntFlag
Enhanced Rx FIFO overflow Interrupt Flag.

enumerator kFLEXCAN_ERxFifoWatermarkIntFlag
Enhanced Rx FIFO watermark Interrupt Flag.

enumerator kFLEXCAN_ERxFifoDataAvlIntFlag
Enhanced Rx FIFO data available Interrupt Flag.

enumerator kFLEXCAN_ERxFifoEmptyFlag
Enhanced Rx FIFO empty status.

enumerator kFLEXCAN_ERxFifoFullFlag
Enhanced Rx FIFO full status.

enumerator kFLEXCAN_HostAccessNonCorrectableErrorIntFlag
Host Access With Non-Correctable Error Interrupt Flag.

enumerator kFLEXCAN_FlexCanAccessNonCorrectableErrorIntFlag
FlexCAN Access With Non-Correctable Error Interrupt Flag.

enumerator kFLEXCAN_CorrectableErrorIntFlag
Correctable Error Interrupt Flag.

enumerator kFLEXCAN_HostAccessNonCorrectableErrorOverrunFlag
Host Access With Non-Correctable Error Interrupt Overrun Flag.

enumerator kFLEXCAN_FlexCanAccessNonCorrectableErrorOverrunFlag
FlexCAN Access With Non-Correctable Error Interrupt Overrun Flag.

enumerator kFLEXCAN_CorrectableErrorOverrunFlag
Correctable Error Interrupt Overrun Flag.

enumerator kFLEXCAN_AllMemoryErrorIntFlag
All Memory Error Interrupt Flags.

enumerator kFLEXCAN_AllMemoryErrorFlag
All Memory Error Flags.

enum _flexcan_error_flags

FlexCAN error status flags.

The FlexCAN Error Status enumerations is used to report current error of the FlexCAN bus. This enumerations should be used with KFLEXCAN_ErrorFlag in *_flexcan_flags* enumerations to ditermine which error is generated.

Values:

enumerator kFLEXCAN_FDStuffingError

Stuffing Error.

enumerator kFLEXCAN_FDFormError

Form Error.

enumerator kFLEXCAN_FDCrcError

Cyclic Redundancy Check Error.

enumerator kFLEXCAN_FDBit0Error

Unable to send dominant bit.

enumerator kFLEXCAN_FDBit1Error

Unable to send recessive bit.

enumerator kFLEXCAN_TxErrorWarningFlag

Tx Error Warning Status.

enumerator kFLEXCAN_RxErrorWarningFlag

Rx Error Warning Status.

enumerator kFLEXCAN_StuffingError

Stuffing Error.

enumerator kFLEXCAN_FormError

Form Error.

enumerator kFLEXCAN_CrcError

Cyclic Redundancy Check Error.

enumerator kFLEXCAN_AckError

Received no ACK on transmission.

enumerator kFLEXCAN_Bit0Error

Unable to send dominant bit.

enumerator kFLEXCAN_Bit1Error

Unable to send recessive bit.

FlexCAN Legacy Rx FIFO status flags.

The FlexCAN Legacy Rx FIFO Status enumerations are used to determine the status of the Rx FIFO. Because Rx FIFO occupy the MB0 ~ MB7 (Rx Fifo filter also occupies more Message Buffer space), Rx FIFO status flags are mapped to the corresponding Message Buffer status flags.

Values:

enumerator kFLEXCAN_RxFifoOverflowFlag
Rx FIFO overflow flag.

enumerator kFLEXCAN_RxFifoWarningFlag
Rx FIFO almost full flag.

enumerator kFLEXCAN_RxFifoFrameAvlFlag
Frames available in Rx FIFO flag.

enum _flexcan_memory_error_type
FlexCAN Memory Error Type.

Values:

enumerator kFLEXCAN_CorrectableError
The memory error is correctable which means on bit error.

enumerator kFLEXCAN_NonCorrectableError
The memory error is non-correctable which means two bit errors.

enum _flexcan_memory_access_type
FlexCAN Memory Access Type.

Values:

enumerator kFLEXCAN_MoveOutFlexCanAccess
The memory error was detected during move-out FlexCAN access.

enumerator kFLEXCAN_MoveInAccess
The memory error was detected during move-in FlexCAN access.

enumerator kFLEXCAN_TxArbitrationAccess
The memory error was detected during Tx Arbitration FlexCAN access.

enumerator kFLEXCAN_RxMatchingAccess
The memory error was detected during Rx Matching FlexCAN access.

enumerator kFLEXCAN_MoveOutHostAccess
The memory error was detected during Rx Matching Host (CPU) access.

enum _flexcan_byte_error_syndrome
FlexCAN Memory Error Byte Syndrome.

Values:

enumerator kFLEXCAN_NoError
No bit error in this byte.

enumerator kFLEXCAN_ParityBits0Error
Parity bit 0 error in this byte.

enumerator kFLEXCAN_ParityBits1Error
Parity bit 1 error in this byte.

enumerator kFLEXCAN_ParityBits2Error
Parity bit 2 error in this byte.

enumerator kFLEXCAN_ParityBits3Error
Parity bit 3 error in this byte.

enumerator kFLEXCAN_ParityBits4Error
Parity bit 4 error in this byte.

enumerator kFLEXCAN_DataBits0Error
Data bit 0 error in this byte.

enumerator kFLEXCAN_DataBits1Error
Data bit 1 error in this byte.

enumerator kFLEXCAN_DataBits2Error
Data bit 2 error in this byte.

enumerator kFLEXCAN_DataBits3Error
Data bit 3 error in this byte.

enumerator kFLEXCAN_DataBits4Error
Data bit 4 error in this byte.

enumerator kFLEXCAN_DataBits5Error
Data bit 5 error in this byte.

enumerator kFLEXCAN_DataBits6Error
Data bit 6 error in this byte.

enumerator kFLEXCAN_DataBits7Error
Data bit 7 error in this byte.

enumerator kFLEXCAN_AllZeroError
All-zeros non-correctable error in this byte.

enumerator kFLEXCAN_AllOneError
All-ones non-correctable error in this byte.

enumerator kFLEXCAN_NonCorrectableErrors
Non-correctable error in this byte.

enum _flexcan_pn_match_source
FlexCAN Pretended Networking match source selection.
Values:

enumerator kFLEXCAN_PNMatSrcID
Message match with ID filtering.

enumerator kFLEXCAN_PNMatSrcIDAndData
Message match with ID filtering and payload filtering.

enum _flexcan_pn_match_mode
FlexCAN Pretended Networking mode match type.
Values:

enumerator kFLEXCAN_PNMatModeEqual
Match upon ID/Payload contents against an exact target value.

enumerator kFLEXCAN_PNMatModeGreater
Match upon an ID/Payload value greater than or equal to a specified target value.

enumerator kFLEXCAN_PNMatModeSmaller
Match upon an ID/Payload value smaller than or equal to a specified target value.

enumerator kFLEXCAN_PNMatModeRange
Match upon an ID/Payload value inside a range, greater than or equal to a specified lower limit, and smaller than or equal to a specified upper limit

typedef enum *_flexcan_frame_format* flexcan_frame_format_t
FlexCAN frame format.

typedef enum *_flexcan_frame_type* flexcan_frame_type_t
FlexCAN frame type.

typedef enum *_flexcan_clock_source* flexcan_clock_source_t
FlexCAN clock source.

Deprecated:
Do not use the kFLEXCAN_ClkSrcOs. It has been superceded kFLEXCAN_ClkSrc0
Do not use the kFLEXCAN_ClkSrcPeri. It has been superceded kFLEXCAN_ClkSrc1

typedef enum *_flexcan_wake_up_source* flexcan_wake_up_source_t
FlexCAN wake up source.

typedef enum *_flexcan_endianness* flexcan_endianness_t

FlexCAN payload endianness.

typedef enum *_flexcan_MB_timestamp_base* flexcan_MB_timestamp_base_t

FlexCAN timebase used for capturing 16-bit TIME_STAMP field of message buffer.

typedef enum *_flexcan_capture_point* flexcan_capture_point_t

FlexCAN capture point of 32-bit high resolution timebase during a CAN frame.

typedef enum *_flexcan_rx_fifo_filter_type* flexcan_rx_fifo_filter_type_t

FlexCAN Rx Fifo Filter type.

typedef enum *_flexcan_mb_size* flexcan_mb_size_t

FlexCAN Message Buffer Payload size.

typedef enum *_flexcan_efifo_dma_per_read_length* flexcan_efifo_dma_per_read_length_t

FlexCAN Enhanced Rx Fifo DMA transfer per read length enumerations.

typedef enum *_flexcan_rx_fifo_priority* flexcan_rx_fifo_priority_t

FlexCAN Enhanced/Legacy Rx FIFO priority.

The matching process starts from the Rx MB(or Enhanced/Legacy Rx FIFO) with higher priority. If no MB(or Enhanced/Legacy Rx FIFO filter) is satisfied, the matching process goes on with the Enhanced/Legacy Rx FIFO(or Rx MB) with lower priority.

typedef enum *_flexcan_memory_error_type* flexcan_memory_error_type_t

FlexCAN Memory Error Type.

typedef enum *_flexcan_memory_access_type* flexcan_memory_access_type_t

FlexCAN Memory Access Type.

typedef enum *_flexcan_byte_error_syndrome* flexcan_byte_error_syndrome_t

FlexCAN Memory Error Byte Syndrome.

typedef struct *_flexcan_memory_error_report_status* flexcan_memory_error_report_status_t

FlexCAN memory error register status structure.

This structure contains the memory access properties that caused a memory error access. It is used as the parameter of *FLEXCAN_GetMemoryErrorReportStatus()* function. And user can use FLEXCAN_GetMemoryErrorReportStatus to get the status of the last memory error access.

typedef struct *_flexcan_frame* flexcan_frame_t

FlexCAN message frame structure.

typedef struct *_flexcan_fd_frame* flexcan_fd_frame_t

CAN FD message frame structure.

The CAN FD message supporting up to sixty four bytes can be used for a data frame, depending on the length selected for the message buffers. The length should be a enumeration member, see *_flexcan_fd_frame_length*.

typedef struct *_flexcan_timing_config* flexcan_timing_config_t

FlexCAN protocol timing characteristic configuration structure.

typedef struct *_flexcan_config* flexcan_config_t

FlexCAN module configuration structure.

Deprecated:

Do not use the baudRate. It has been superceded bitRate

Do not use the baudRateFD. It has been superceded bitRateFD

typedef struct *_flexcan_rx_mb_config* flexcan_rx_mb_config_t

FlexCAN Receive Message Buffer configuration structure.

This structure is used as the parameter of *FLEXCAN_SetRxMbConfig()* function. The *FLEXCAN_SetRxMbConfig()* function is used to configure FlexCAN Receive Message Buffer. The function abort previous receiving process, clean the Message Buffer and activate the Rx Message Buffer using given Message Buffer setting.

typedef enum *_flexcan_pn_match_source* flexcan_pn_match_source_t

FlexCAN Pretended Networking match source selection.

typedef enum *_flexcan_pn_match_mode* flexcan_pn_match_mode_t

FlexCAN Pretended Networking mode match type.

typedef struct *_flexcan_pn_config* flexcan_pn_config_t

FlexCAN Pretended Networking configuration structure.

This structure is used as the parameter of *FLEXCAN_SetPNConfig()* function. The *FLEXCAN_SetPNConfig()* function is used to configure FlexCAN Networking work mode.

typedef struct *_flexcan_rx_fifo_config* flexcan_rx_fifo_config_t

FlexCAN Legacy Rx FIFO configuration structure.

typedef struct *_flexcan_enhanced_rx_fifo_std_id_filter* flexcan_enhanced_rx_fifo_std_id_filter_t

FlexCAN Enhanced Rx FIFO Standard ID filter element structure.

typedef struct *_flexcan_enhanced_rx_fifo_ext_id_filter* flexcan_enhanced_rx_fifo_ext_id_filter_t

FlexCAN Enhanced Rx FIFO Extended ID filter element structure.

typedef struct *_flexcan_enhanced_rx_fifo_config* flexcan_enhanced_rx_fifo_config_t

FlexCAN Enhanced Rx FIFO configuration structure.

typedef struct *_flexcan_mb_transfer* flexcan_mb_transfer_t

FlexCAN Message Buffer transfer.

typedef struct *_flexcan_fifo_transfer* flexcan_fifo_transfer_t

FlexCAN Rx FIFO transfer.

typedef struct *_flexcan_handle* flexcan_handle_t

FlexCAN handle structure definition.

typedef void (*flexcan_transfer_callback_t)(CAN_Type *base, *flexcan_handle_t* *handle, *status_t* status, uint64_t result, void *userData)

FLEXCAN_WAIT_TIMEOUT

FLEXCAN_POLLING_TIMEOUT

Max loops to wait for polling transfer.

FLEXCAN_MODULE_TIMEOUT

Max loops to wait for FlexCAN register access complete.

FLEXCAN_MB_BUSY_TIMEOUT

Max loops to wait for FlexCAN RX Message Buffer busy.

DLC_LENGTH_DECODE(dlc)

FlexCAN frame length helper macro.

FLEXCAN_ID_STD(id)

FlexCAN Frame ID helper macro.

Standard Frame ID helper macro.

FLEXCAN_ID_EXT(id)

Extend Frame ID helper macro.

FLEXCAN_RX_MB_STD_MASK(id, rtr, ide)

FlexCAN Rx Message Buffer Mask helper macro.

Standard Rx Message Buffer Mask helper macro.

FLEXCAN_RX_MB_EXT_MASK(id, rtr, ide)

Extend Rx Message Buffer Mask helper macro.

FLEXCAN_RX_FIFO_STD_MASK_TYPE_A(id, rtr, ide)

FlexCAN Legacy Rx FIFO Mask helper macro.

Standard Rx FIFO Mask helper macro Type A helper macro.

FLEXCAN_RX_FIFO_STD_MASK_TYPE_B_HIGH(id, rtr, ide)

Standard Rx FIFO Mask helper macro Type B upper part helper macro.

FLEXCAN_RX_FIFO_STD_MASK_TYPE_B_LOW(id, rtr, ide)

Standard Rx FIFO Mask helper macro Type B lower part helper macro.

FLEXCAN_RX_FIFO_STD_MASK_TYPE_C_HIGH(id)

Standard Rx FIFO Mask helper macro Type C upper part helper macro.

FLEXCAN_RX_FIFO_STD_MASK_TYPE_C_MID_HIGH(id)

Standard Rx FIFO Mask helper macro Type C mid-upper part helper macro.

FLEXCAN_RX_FIFO_STD_MASK_TYPE_C_MID_LOW(id)

Standard Rx FIFO Mask helper macro Type C mid-lower part helper macro.

FLEXCAN_RX_FIFO_STD_MASK_TYPE_C_LOW(id)

Standard Rx FIFO Mask helper macro Type C lower part helper macro.

FLEXCAN_RX_FIFO_EXT_MASK_TYPE_A(id, rtr, ide)

Extend Rx FIFO Mask helper macro Type A helper macro.

FLEXCAN_RX_FIFO_EXT_MASK_TYPE_B_HIGH(id, rtr, ide)
Extend Rx FIFO Mask helper macro Type B upper part helper macro.

FLEXCAN_RX_FIFO_EXT_MASK_TYPE_B_LOW(id, rtr, ide)
Extend Rx FIFO Mask helper macro Type B lower part helper macro.

FLEXCAN_RX_FIFO_EXT_MASK_TYPE_C_HIGH(id)
Extend Rx FIFO Mask helper macro Type C upper part helper macro.

FLEXCAN_RX_FIFO_EXT_MASK_TYPE_C_MID_HIGH(id)
Extend Rx FIFO Mask helper macro Type C mid-upper part helper macro.

FLEXCAN_RX_FIFO_EXT_MASK_TYPE_C_MID_LOW(id)
Extend Rx FIFO Mask helper macro Type C mid-lower part helper macro.

FLEXCAN_RX_FIFO_EXT_MASK_TYPE_C_LOW(id)
Extend Rx FIFO Mask helper macro Type C lower part helper macro.

FLEXCAN_RX_FIFO_STD_FILTER_TYPE_A(id, rtr, ide)
FlexCAN Rx FIFO Filter helper macro.

Standard Rx FIFO Filter helper macro Type A helper macro.

FLEXCAN_RX_FIFO_STD_FILTER_TYPE_B_HIGH(id, rtr, ide)
Standard Rx FIFO Filter helper macro Type B upper part helper macro.

FLEXCAN_RX_FIFO_STD_FILTER_TYPE_B_LOW(id, rtr, ide)
Standard Rx FIFO Filter helper macro Type B lower part helper macro.

FLEXCAN_RX_FIFO_STD_FILTER_TYPE_C_HIGH(id)
Standard Rx FIFO Filter helper macro Type C upper part helper macro.

FLEXCAN_RX_FIFO_STD_FILTER_TYPE_C_MID_HIGH(id)
Standard Rx FIFO Filter helper macro Type C mid-upper part helper macro.

FLEXCAN_RX_FIFO_STD_FILTER_TYPE_C_MID_LOW(id)
Standard Rx FIFO Filter helper macro Type C mid-lower part helper macro.

FLEXCAN_RX_FIFO_STD_FILTER_TYPE_C_LOW(id)
Standard Rx FIFO Filter helper macro Type C lower part helper macro.

FLEXCAN_RX_FIFO_EXT_FILTER_TYPE_A(id, rtr, ide)
Extend Rx FIFO Filter helper macro Type A helper macro.

FLEXCAN_RX_FIFO_EXT_FILTER_TYPE_B_HIGH(id, rtr, ide)
Extend Rx FIFO Filter helper macro Type B upper part helper macro.

FLEXCAN_RX_FIFO_EXT_FILTER_TYPE_B_LOW(id, rtr, ide)
Extend Rx FIFO Filter helper macro Type B lower part helper macro.

FLEXCAN_RX_FIFO_EXT_FILTER_TYPE_C_HIGH(id)
Extend Rx FIFO Filter helper macro Type C upper part helper macro.

FLEXCAN_RX_FIFO_EXT_FILTER_TYPE_C_MID_HIGH(id)
Extend Rx FIFO Filter helper macro Type C mid-upper part helper macro.

FLEXCAN_RX_FIFO_EXT_FILTER_TYPE_C_MID_LOW(id)
Extend Rx FIFO Filter helper macro Type C mid-lower part helper macro.

FLEXCAN_RX_FIFO_EXT_FILTER_TYPE_C_LOW(id)
Extend Rx FIFO Filter helper macro Type C lower part helper macro.

ENHANCED_RX_FIFO_FSCH(x)
FlexCAN Enhanced Rx FIFO Filter and Mask helper macro.

RTR_STD_HIGH(x)

RTR_STD_LOW(x)

RTR_EXT(x)

ID_STD_LOW(id)

ID_STD_HIGH(id)

ID_EXT(id)

FLEXCAN_ENHANCED_RX_FIFO_STD_MASK_AND_FILTER(id, rtr, id_mask, rtr_mask)
Standard ID filter element with filter + mask scheme.

FLEXCAN_ENHANCED_RX_FIFO_STD_FILTER_WITH_RANGE(id_upper, rtr, id_lower, rtr_mask)
Standard ID filter element with filter range.

FLEXCAN_ENHANCED_RX_FIFO_STD_TWO_FILTERS(id1, rtr1, id2, rtr2)
Standard ID filter element with two filters without masks.

FLEXCAN_ENHANCED_RX_FIFO_EXT_MASK_AND_FILTER_LOW(id, rtr)
Extended ID filter element with filter + mask scheme low word.

FLEXCAN_ENHANCED_RX_FIFO_EXT_MASK_AND_FILTER_HIGH(id_mask, rtr_mask)
Extended ID filter element with filter + mask scheme high word.

FLEXCAN_ENHANCED_RX_FIFO_EXT_FILTER_WITH_RANGE_LOW(id_upper, rtr)
Extended ID filter element with range scheme low word.

FLEXCAN_ENHANCED_RX_FIFO_EXT_FILTER_WITH_RANGE_HIGH(id_lower, rtr_mask)
Extended ID filter element with range scheme high word.

FLEXCAN_ENHANCED_RX_FIFO_EXT_TWO_FILTERS_LOW(id2, rtr2)
Extended ID filter element with two filters without masks low word.

FLEXCAN_ENHANCED_RX_FIFO_EXT_TWO_FILTERS_HIGH(id1, rtr1)
Extended ID filter element with two filters without masks high word.

FLEXCAN_PN_STD_MASK(id, rtr)
FlexCAN Pretended Networking ID Mask helper macro.

Standard Rx Message Buffer Mask helper macro.

FLEXCAN_PN_EXT_MASK(id, rtr)
Extend Rx Message Buffer Mask helper macro.

FLEXCAN_PN_INT_MASK(x)
FlexCAN interrupt/status flag helper macro.

FLEXCAN_PN_INT_UNMASK(x)

FLEXCAN_PN_STATUS_MASK(x)

FLEXCAN_PN_STATUS_UNMASK(x)

FLEXCAN_EFIFO_INT_MASK(x)

FLEXCAN_EFIFO_INT_UNMASK(x)

FLEXCAN_EFIFO_STATUS_MASK(x)

FLEXCAN_EFIFO_STATUS_UNMASK(x)

FLEXCAN_MECR_INT_MASK(x)

FLEXCAN_MECR_INT_UNMASK(x)

FLEXCAN_MECR_STATUS_MASK(x)

FLEXCAN_MECR_STATUS_UNMASK(x)

FLEXCAN_ERROR_AND_STATUS_INT_FLAG

FLEXCAN_PNWAKE_UP_FLAG

FLEXCAN_WAKE_UP_FLAG

FLEXCAN_MEMORY_ERROR_INT_FLAG

FLEXCAN_ENHANCED_RX_FIFO_INT_FLAG

FlexCAN Enhanced Rx FIFO base address helper macro.

E_RX_FIFO(base)

FLEXCAN_CALLBACK(x)

FlexCAN transfer callback function.

The FlexCAN transfer callback returns a value from the underlying layer. If the status equals to kStatus_FLEXCAN_ErrorStatus, the result parameter is the Content of FlexCAN status register which can be used to get the working status(or error status) of FlexCAN module. If the status equals to other FlexCAN Message Buffer transfer status, the result is the index of Message Buffer that generate transfer event. If the status equals to other FlexCAN Message Buffer transfer status, the result is meaningless and should be Ignored.

struct __flexcan_memory_error_report_status

#include <fsl_flexcan.h> FlexCAN memory error register status structure.

This structure contains the memory access properties that caused a memory error access. It is used as the parameter of *FLEXCAN_GetMemoryErrorReportStatus()* function. And user can use FLEXCAN_GetMemoryErrorReportStatus to get the status of the last memory error access.

Public Members

flexcan_memory_error_type_t errorType

The type of memory error that giving rise to the report.

flexcan_memory_access_type_t accessType

The type of memory access that giving rise to the memory error.

uint16_t accessAddress

The address where memory error detected.

uint32_t errorData

The raw data word read from memory with error.

struct _flexcan_frame

#include <fsl_flexcan.h> FlexCAN message frame structure.

struct _flexcan_fd_frame

#include <fsl_flexcan.h> CAN FD message frame structure.

The CAN FD message supporting up to sixty four bytes can be used for a data frame, depending on the length selected for the message buffers. The length should be a enumeration member, see *_flexcan_fd_frame_length*.

Public Members

uint32_t idhit

Note: ID HIT offset is changed dynamically according to data length code (DLC), when DLC is 15, they will be located below. Using FLEXCAN_FixEnhancedRxFifoFrameIdHit API is recommended to ensure this idhit value is correct. CAN Enhanced Rx FIFO filter hit id (This value is only used in Enhanced Rx FIFO receive mode).

uint32_t hrtimestamp

Note: HR timestamp offset is changed dynamically according to data length code (DLC). External 32-bit on-chip timer high-resolution timestamp.

struct _flexcan_timing_config

#include <fsl_flexcan.h> FlexCAN protocol timing characteristic configuration structure.

Public Members

uint32_t preDivider

Classic CAN or CAN FD nominal phase bit rate prescaler.

uint32_t rJumpwidth

Classic CAN or CAN FD nominal phase Re-sync Jump Width.

uint32_t phaseSeg1

Classic CAN or CAN FD nominal phase Segment 1.

uint32_t phaseSeg2

Classic CAN or CAN FD nominal phase Segment 2.

uint32_t propSeg

Classic CAN or CAN FD nominal phase Propagation Segment.

uint32_t fpreDivider
: CAN FD data phase bit rate prescaler.

uint32_t frJumpwidth
: CAN FD data phase Re-sync Jump Width.

uint32_t fphaseSeg1
: CAN FD data phase Phase Segment 1.

uint32_t fphaseSeg2
: CAN FD data phase Phase Segment 2.

uint32_t fpropSeg
: CAN FD data phase Propagation Segment.

struct __flexcan__config
: *#include <fsl_flexcan.h>* FlexCAN module configuration structure.

Deprecated:
: Do not use the baudRate. It has been superceded bitRate
Do not use the baudRateFD. It has been superceded bitRateFD

Public Members

flexcan_clock_source_t clkSrc
: Clock source for FlexCAN Protocol Engine.

flexcan_wake_up_source_t wakeupSrc
: Wake up source selection.

uint8_t maxMbNum
: The maximum number of Message Buffers used by user.

bool enableLoopBack
: Enable or Disable Loop Back Self Test Mode.

bool enableTimerSync
: Enable or Disable Timer Synchronization.

bool enableIndividMask
: Enable or Disable Rx Individual Mask and Queue feature.

bool disableSelfReception
: Enable or Disable Self Reflection.

bool enableListenOnlyMode
: Enable or Disable Listen Only Mode.

bool enableDoze

Enable or Disable Doze Mode.

bool enablePretendedeNetworking

Enable or Disable the Pretended Networking mode.

bool enableMemoryErrorControl

Enable or Disable the memory errors detection and correction mechanism.

bool enableNonCorrectableErrorEnterFreeze

Enable or Disable Non-Correctable Errors In FlexCAN Access Put Device In Freeze Mode.

bool enableTransceiverDelayMeasure

Enable or Disable the transceiver delay measurement, when it is enabled, then the secondary sample point position is determined by the sum of the transceiver delay measurement plus the enhanced TDC offset.

bool enableRemoteRequestFrameStored

true: Store Remote Request Frame in the same fashion of data frame. false: Generate an automatic Remote Response Frame.

bool enableThreeSamplingMode

true: Three samples are used to determine the value of the received bit, providing noise immunity against fast transient changes. false: One sample is used to determine the value of the received bit.

bool disableBusOffAutoRecovery

true: Automatic recovering from Bus-Off state is disabled. false: Automatic recovering from Bus-Off state is enabled according to CAN Specification.

uint8_t txArbitrationStartDelay

Determines how many CAN bits the transmission arbitration process start point can be delayed from the first bit of CRC field on CAN bus, valid range 0-31.

bool enableEntireArbitrationCompare

true: Enable Entire Frame Arbitration Field Comparison for Rx MB. The IDE and RTR fields of the RX MBs are compared to their corresponding bits within the incoming frame (mask bits apply). false: The IDE field of the RX MB filter is always compared and RTR is never compared despite mask bits.

flexcan_endianness_t payloadEndianness

Selects the byte order for the payload of transmit and receive frames, see *flexcan_endianness_t*.

bool enableExternalTimeTick

true: External time tick clocks the free-running timer. false: FlexCAN bit clock clocks the free-running timer.

flexcan_MB_timestamp_base_t captureTimeBase

Timebase of message buffer 16-bit TIME_STAMP field.

flexcan_capture_point_t capturePoint

Point in time when 32-bit timebase is captured during CAN frame.

struct _flexcan_rx_mb_config

#include <fsl_flexcan.h> FlexCAN Receive Message Buffer configuration structure.

This structure is used as the parameter of *FLEXCAN_SetRxMbConfig()* function. The *FLEXCAN_SetRxMbConfig()* function is used to configure FlexCAN Receive Message Buffer. The function abort previous receiving process, clean the Message Buffer and activate the Rx Message Buffer using given Message Buffer setting.

Public Members

uint32_t id

CAN Message Buffer Frame Identifier, should be set using *FLEXCAN_ID_EXT()* or *FLEXCAN_ID_STD()* macro.

flexcan_frame_format_t format

CAN Frame Identifier *format(Standard of Extend)*.

flexcan_frame_type_t type

CAN Frame Type(Data or Remote for classical CAN only).

struct _flexcan_pn_config

#include <fsl_flexcan.h> FlexCAN Pretended Networking configuration structure.

This structure is used as the parameter of *FLEXCAN_SetPNConfig()* function. The *FLEXCAN_SetPNConfig()* function is used to configure FlexCAN Networking work mode.

Public Members

bool enableTimeout

Enable or Disable timeout event trigger wakeup.

uint16_t timeoutValue

The timeout value that generates a wakeup event, the counter timer is incremented based on 64 times the CAN Bit Time unit.

bool enableMatch

Enable or Disable match event trigger wakeup.

flexcan_pn_match_source_t matchSrc

Selects the match source (ID and/or data match) to trigger wakeup.

uint8_t matchNum

The number of times a given message must match the predefined ID and/or data before generating a wakeup event, range in 0x1 ~ 0xFF.

flexcan_pn_match_mode_t idMatchMode

The ID match type.

flexcan_pn_match_mode_t dataMatchMode

The data match type.

uint32_t idLower

The ID target values 1 which used either for ID match “equal to”, “smaller than”, “greater than” comparisons, or as the lower limit value in ID match “range detection”.

uint32_t idUpper

The ID target values 2 which used only as the upper limit value in ID match “range detection” or used to store the ID mask in “equal to”.

uint8_t lengthLower

The lower limit for length of data bytes which used only in data match “range detection”. Range in 0x0 ~ 0x8.

uint8_t lengthUpper

The upper limit for length of data bytes which used only in data match “range detection”. Range in 0x0 ~ 0x8.

struct __flexcan__rx__fifo__config

#include <fsl_flexcan.h> FlexCAN Legacy Rx FIFO configuration structure.

Public Members

uint32_t *idFilterTable

Pointer to the FlexCAN Legacy Rx FIFO identifier filter table.

uint8_t idFilterNum

The FlexCAN Legacy Rx FIFO Filter elements quantity.

flexcan_rx_fifo_filter_type_t idFilterType

The FlexCAN Legacy Rx FIFO Filter type.

flexcan_rx_fifo_priority_t priority

The FlexCAN Legacy Rx FIFO receive priority.

struct __flexcan__enhanced__rx__fifo__std__id__filter

#include <fsl_flexcan.h> FlexCAN Enhanced Rx FIFO Standard ID filter element structure.

Public Members

uint32_t filterType

FlexCAN internal Free-Running Counter Time Stamp.

uint32_t rtr1

CAN FD frame data length code (DLC), range see *_flexcan_fd_frame_length*, When the length <= 8, it equal to the data length, otherwise the number of valid frame data is not equal to the length value. user can use *DLC_LENGTH_DECODE(length)* macro to get the number of valid data bytes.

uint32_t std1

CAN Frame Type(DATA or REMOTE).

uint32_t rtr2

CAN Frame Identifier(STD or EXT format).

uint32_t std2

Substitute Remote request.

struct __flexcan_enhanced_rx_fifo_ext_id_filter

#include <fsl_flexcan.h> FlexCAN Enhanced Rx FIFO Extended ID filter element structure.

Public Members

uint32_t filterType

FlexCAN internal Free-Running Counter Time Stamp.

uint32_t rtr1

CAN FD frame data length code (DLC), range see *_flexcan_fd_frame_length*, When the length <= 8, it equal to the data length, otherwise the number of valid frame data is not equal to the length value. user can use *DLC_LENGTH_DECODE(length)* macro to get the number of valid data bytes.

uint32_t std1

CAN Frame Type(DATA or REMOTE).

uint32_t rtr2

CAN Frame Identifier(STD or EXT format).

uint32_t std2

Substitute Remote request.

struct __flexcan_enhanced_rx_fifo_config

#include <fsl_flexcan.h> FlexCAN Enhanced Rx FIFO configuration structure.

Public Members

uint32_t *idFilterTable

Pointer to the FlexCAN Enhanced Rx FIFO identifier filter table, each table member occupies 32 bit word, table size should be equal to idFilterNum. There are two types of Enhanced Rx FIFO filter elements that can be stored in table : extended-ID filter element (1 word, occupie 1 table members) and standard-ID filter element (2 words, occupies 2 table members), the extended-ID filter element needs to be placed in front of the table.

uint8_t idFilterPairNum

idFilterPairNum is the Enhanced Rx FIFO identifier filter element pair numbers, each pair of filter elements occupies 2 words and can consist of one extended ID filter element or two standard ID filter elements.

uint8_t extendIdFilterNum

The number of extended ID filter element items in the FlexCAN enhanced Rx FIFO identifier filter table, each extended-ID filter element occupies 2 words, extendIdFilterNum need less than or equal to idFilterPairNum.

uint8_t fifoWatermark

(fifoWatermark + 1) is the minimum number of CAN messages stored in the Enhanced RX FIFO which can trigger FIFO watermark interrupt or a DMA request.

flexcan_efifo_dma_per_read_length_t dmaPerReadLength

Define the length of each read of the Enhanced RX FIFO element by the DAM, see *_flexcan_fd_frame_length*.

flexcan_rx_fifo_priority_t priority

The FlexCAN Enhanced Rx FIFO receive priority.

struct __flexcan_mb_transfer

#include <fsl_flexcan.h> FlexCAN Message Buffer transfer.

Public Members

flexcan_frame_t *frame

The buffer of CAN Message to be transfer.

uint8_t mbIdx

The index of Message buffer used to transfer Message.

struct __flexcan_fifo_transfer

#include <fsl_flexcan.h> FlexCAN Rx FIFO transfer.

Public Members

flexcan_fd_frame_t *framefd

The buffer of CAN Message to be received from Enhanced Rx FIFO.

flexcan_frame_t *frame
The buffer of CAN Message to be received from Legacy Rx FIFO.

size_t frameNum
Depth of CAN Message receive array of Legacy or Enhanced Rx FIFO.

struct __flexcan_handle
#include <fsl_flexcan.h> FlexCAN handle structure.

Public Members

flexcan_transfer_callback_t callback
Callback function.

void *userData
FlexCAN callback function parameter.

flexcan_frame_t *volatile mbFrameBuf[CAN_WORD1_COUNT]
The buffer for received CAN data from Message Buffers.

flexcan_fd_frame_t *volatile mbFDFrameBuf[CAN_WORD1_COUNT]
The buffer for received CAN FD data from Message Buffers.

flexcan_frame_t *volatile rxFifoFrameBuf
The buffer for received CAN data from Legacy Rx FIFO.

flexcan_fd_frame_t *volatile rxFifoFDFrameBuf
The buffer for received CAN FD data from Enhanced Rx FIFO.

size_t rxFifoFrameNum
The number of CAN messages remaining to be received from Legacy or Enhanced Rx FIFO.

size_t rxFifoTransferTotalNum
Total CAN Message number need to be received from Legacy or Enhanced Rx FIFO.

volatile uint8_t mbState[CAN_WORD1_COUNT]
Message Buffer transfer state.

volatile uint8_t rxFifoState
Rx FIFO transfer state.

volatile uint32_t timestamp[CAN_WORD1_COUNT]
Mailbox transfer timestamp.

struct byteStatus

Public Members

bool byteIsRead

The byte n (0~3) was read or not. The type of error and which bit in byte (n) is affected by the error.

struct ___unnamed22___

Public Members

uint32_t timestamp

FlexCAN internal Free-Running Counter Time Stamp.

uint32_t length

CAN frame data length in bytes (Range: 0~8).

uint32_t type

CAN Frame Type(DATA or REMOTE).

uint32_t format

CAN Frame Identifier(STD or EXT format).

uint32_t ___pad0___

Reserved.

uint32_t idhit

CAN Rx FIFO filter hit id(This value is only used in Rx FIFO receive mode).

struct ___unnamed24___

Public Members

uint32_t id

CAN Frame Identifier, should be set using *FLEXCAN_ID_EXT()* or *FLEXCAN_ID_STD()* macro.

uint32_t ___pad0___

Reserved.

union ___unnamed26___

Public Members

struct __flexcan__frame

struct _flexcan_frame

struct ___unnamed28___

Public Members

uint32_t dataWord0
CAN Frame payload word0.

uint32_t dataWord1
CAN Frame payload word1.

struct ___unnamed30___

Public Members

uint8_t dataByte3
CAN Frame payload byte3.

uint8_t dataByte2
CAN Frame payload byte2.

uint8_t dataByte1
CAN Frame payload byte1.

uint8_t dataByte0
CAN Frame payload byte0.

uint8_t dataByte7
CAN Frame payload byte7.

uint8_t dataByte6
CAN Frame payload byte6.

uint8_t dataByte5
CAN Frame payload byte5.

uint8_t dataByte4
CAN Frame payload byte4.

struct ___unnamed32___

Public Members

uint32_t timestamp

FlexCAN internal Free-Running Counter Time Stamp.

uint32_t length

CAN FD frame data length code (DLC), range see *_flexcan_fd_frame_length*, When the length <= 8, it equal to the data length, otherwise the number of valid frame data is not equal to the length value. user can use *DLC_LENGTH_DECODE(length)* macro to get the number of valid data bytes.

uint32_t type

CAN Frame Type(DATA only).

uint32_t format

CAN Frame Identifier(STD or EXT format).

uint32_t srr

Substitute Remote request.

uint32_t esi

Error State Indicator.

uint32_t brs

Bit Rate Switch.

uint32_t edl

Extended Data Length.

struct ___unnamed34___

Public Members

uint32_t id

CAN Frame Identifier, should be set using *FLEXCAN_ID_EXT()* or *FLEXCAN_ID_STD()* macro.

uint32_t ___pad0___

Reserved.

union ___unnamed36___

Public Members

struct _flexcan_fd_frame

struct _flexcan_fd_frame

struct ___unnamed38___

Public Members

uint32_t dataWord[16]
CAN FD Frame payload, 16 double word maximum.

struct ___unnamed40___

Public Members

uint8_t dataByte3
CAN Frame payload byte3.

uint8_t dataByte2
CAN Frame payload byte2.

uint8_t dataByte1
CAN Frame payload byte1.

uint8_t dataByte0
CAN Frame payload byte0.

uint8_t dataByte7
CAN Frame payload byte7.

uint8_t dataByte6
CAN Frame payload byte6.

uint8_t dataByte5
CAN Frame payload byte5.

uint8_t dataByte4
CAN Frame payload byte4.

union ___unnamed42___

Public Members

struct _flexcan_config

struct _flexcan_config

struct ___unnamed44___

Public Members

uint32_t baudRate

FlexCAN bit rate in bps, for classical CAN or CANFD nominal phase.

uint32_t baudRateFD

FlexCAN FD bit rate in bps, for CANFD data phase.

struct ___unnamed46___

Public Members

uint32_t bitRate

FlexCAN bit rate in bps, for classical CAN or CANFD nominal phase.

uint32_t bitRateFD

FlexCAN FD bit rate in bps, for CANFD data phase.

union ___unnamed48___

Public Members

struct _flexcan_pn_config

< The data target values 1 which used either for data match “equal to”, “smaller than”, “greater than” comparisons, or as the lower limit value in data match “range

detection”.

struct _flexcan_pn_config

struct ___unnamed52___

< The data target values 1 which used either for data match “equal to”, “smaller than”, “greater than” comparisons, or as the lower limit value in data match “range

detection”.

Public Members

uint32_t lowerWord0

CAN Frame payload word0.

uint32_t lowerWord1

CAN Frame payload word1.

struct ___unnamed54___

Public Members

uint8_t lowerByte3
: CAN Frame payload byte3.

uint8_t lowerByte2
: CAN Frame payload byte2.

uint8_t lowerByte1
: CAN Frame payload byte1.

uint8_t lowerByte0
: CAN Frame payload byte0.

uint8_t lowerByte7
: CAN Frame payload byte7.

uint8_t lowerByte6
: CAN Frame payload byte6.

uint8_t lowerByte5
: CAN Frame payload byte5.

uint8_t lowerByte4
: CAN Frame payload byte4.

union ___unnamed50___

Public Members

struct __flexcan__pn__config

< The data target values 2 which used only as the upper limit value in data match “range

detection” or used to store the data mask in “equal to”.

struct __flexcan__pn__config

struct ___unnamed56___

< The data target values 2 which used only as the upper limit value in data match “range detection” or used to store the data mask in “equal to”.

Public Members

uint32_t upperWord0
: CAN Frame payload word0.

uint32_t upperWord1
CAN Frame payload word1.

struct ___unnamed58___

Public Members

uint8_t upperByte3
CAN Frame payload byte3.

uint8_t upperByte2
CAN Frame payload byte2.

uint8_t upperByte1
CAN Frame payload byte1.

uint8_t upperByte0
CAN Frame payload byte0.

uint8_t upperByte7
CAN Frame payload byte7.

uint8_t upperByte6
CAN Frame payload byte6.

uint8_t upperByte5
CAN Frame payload byte5.

uint8_t upperByte4
CAN Frame payload byte4.

2.16 FlexCAN eDMA Driver

void FLEXCAN_TransferCreateHandleEDMA(CAN_Type *base, *flexcan_edma_handle_t* *handle, *flexcan_edma_transfer_callback_t* callback, void *userData, *edma_handle_t* *rxFifoEdmaHandle)

Initializes the FlexCAN handle, which is used in transactional functions.

Parameters

- base – FlexCAN peripheral base address.
- handle – Pointer to flexcan_edma_handle_t structure.
- callback – The callback function.
- userData – The parameter of the callback function.
- rxFifoEdmaHandle – User-requested DMA handle for Rx FIFO DMA transfer.

void FLEXCAN_PrepareTransfConfiguration(CAN_Type *base, *flexcan_fifo_transfer_t* *pFifoXfer, *edma_transfer_config_t* *pEdmaConfig)

Prepares the eDMA transfer configuration for FLEXCAN Legacy RX FIFO.

This function prepares the eDMA transfer configuration structure according to FLEXCAN Legacy RX FIFO.

Parameters

- base – FlexCAN peripheral base address.
- pFifoXfer – FlexCAN Rx FIFO EDMA transfer structure, see *flexcan_fifo_transfer_t*.
- pEdmaConfig – The user configuration structure of type edma_transfer_t.

status_t FLEXCAN_StartTransferDatafromRxFIFO(CAN_Type *base, *flexcan_edma_handle_t* *handle, *edma_transfer_config_t* *pEdmaConfig)

Start Transfer Data from the FLEXCAN Legacy Rx FIFO using eDMA.

This function to Update edma transfer confiugration and Start eDMA transfer

Parameters

- base – FlexCAN peripheral base address.
- handle – Pointer to flexcan_edma_handle_t structure.
- pEdmaConfig – The user configuration structure of type edma_transfer_t.

Return values

- kStatus_Success – if succeed, others failed.
- kStatus_FLEXCAN_RxFifoBusy – Previous transfer ongoing.

status_t FLEXCAN_TransferReceiveFifoEDMA(CAN_Type *base, *flexcan_edma_handle_t* *handle, *flexcan_fifo_transfer_t* *pFifoXfer)

Receives the CAN Message from the Legacy Rx FIFO using eDMA.

This function receives the CAN Message using eDMA. This is a non-blocking function, which returns right away. After the CAN Message is received, the receive callback function is called.

Parameters

- base – FlexCAN peripheral base address.
- handle – Pointer to flexcan_edma_handle_t structure.
- pFifoXfer – FlexCAN Rx FIFO EDMA transfer structure, see *flexcan_fifo_transfer_t*.

Return values

- kStatus_Success – if succeed, others failed.
- kStatus_FLEXCAN_RxFifoBusy – Previous transfer ongoing.

status_t FLEXCAN_TransferGetReceiveFifoCountEMDA(CAN_Type *base, *flexcan_edma_handle_t* *handle, size_t *count)

Gets the Legacy Rx Fifo transfer status during a interrupt non-blocking receive.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.

- count – Number of CAN messages receive so far by the non-blocking transaction.

Return values

- kStatus_InvalidArgument – count is Invalid.
- kStatus_Success – Successfully return the count.

void FLEXCAN_TransferAbortReceiveFifoEDMA(CAN_Type *base, *flexcan_edma_handle_t* *handle)

Aborts the receive Legacy/Enhanced Rx FIFO process which used eDMA.

This function aborts the receive Legacy/Enhanced Rx FIFO process which used eDMA.

Parameters

- base – FlexCAN peripheral base address.
- handle – Pointer to flexcan_edma_handle_t structure.

status_t FLEXCAN_TransferReceiveEnhancedFifoEDMA(CAN_Type *base, *flexcan_edma_handle_t* *handle, *flexcan_fifo_transfer_t* *pFifoXfer)

Receives the CAN FD Message from the Enhanced Rx FIFO using eDMA.

This function receives the CAN FD Message using eDMA. This is a non-blocking function, which returns right away. After the CAN Message is received, the receive callback function is called.

Parameters

- base – FlexCAN peripheral base address.
- handle – Pointer to flexcan_edma_handle_t structure.
- pFifoXfer – FlexCAN Rx FIFO EDMA transfer structure, see *flexcan_fifo_transfer_t*.

Return values

- kStatus_Success – if succeed, others failed.
- kStatus_FLEXCAN_RxFifoBusy – Previous transfer ongoing.

static inline *status_t* FLEXCAN_TransferGetReceiveEnhancedFifoCountEMDA(CAN_Type *base, *flexcan_edma_handle_t* *handle, size_t *count)

Gets the Enhanced Rx Fifo transfer status during a interrupt non-blocking receive.

Parameters

- base – FlexCAN peripheral base address.
- handle – FlexCAN handle pointer.
- count – Number of CAN messages receive so far by the non-blocking transaction.

Return values

- kStatus_InvalidArgument – count is Invalid.
- kStatus_Success – Successfully return the count.

FSL_FLEXCAN_EDMA_DRIVER_VERSION

FlexCAN EDMA driver version.

typedef struct *_flexcan_edma_handle* flexcan_edma_handle_t

typedef void (*flexcan_edma_transfer_callback_t)(CAN_Type *base, *flexcan_edma_handle_t* *handle, *status_t* status, void *userData)

FlexCAN transfer callback function.

struct _flexcan_edma_handle

#include <fsl_flexcan_edma.h> FlexCAN eDMA handle.

Public Members

flexcan_edma_transfer_callback_t callback

Callback function.

void *userData

FlexCAN callback function parameter.

edma_handle_t *rxFifoEdmaHandle

The EDMA handler for Rx FIFO.

volatile uint8_t rxFifoState

Rx FIFO transfer state.

size_t frameNum

The number of messages that need to be received.

flexcan_fd_frame_t *framefd

Point to the buffer of CAN Message to be received from Enhanced Rx FIFO.

2.17 FlexIO: FlexIO Driver

2.18 Flexio_a-format

Error codes for the A_Format driver.

Values:

enumerator kStatus_FLEXIO_A_FORMAT_TxBusy

Transmitter is busy.

enumerator kStatus_FLEXIO_A_FORMAT_RxBusy

Receiver is busy.

enumerator kStatus_FLEXIO_A_FORMAT_TxIdle

Transmitter is idle.

enumerator kStatus_FLEXIO_A_FORMAT_RxIdle
Receiver is idle.

enumerator kStatus_FLEXIO_A_FORMAT_NotSyncCMD
This Command doesn't support sync mode.

enumerator kStatus_FLEXIO_A_FORMAT_OutOfIDRange
A-format encoder ID is out of range.

enumerator kStatus_FLEXIO_A_FORMAT_RxRingBufferOverrun
A-format RX software ring buffer overrun.

enumerator kStatus_FLEXIO_A_FORMAT_RxHardwareOverrun
A-format RX receiver overrun.

enumerator kStatus_FLEXIO_A_FORMAT_FrameErr
Frame format error.

enumerator kStatus_FLEXIO_A_FORMAT_Timeout
A-format times out.

enumerator kStatus_FLEXIO_A_FORMAT_BaudrateNotSupport
Baudrate is not supported in current clock source

enum _flexio_a_format_encoder_status
Values:

enumerator kFLEXIO_A_FORMAT_ES_NoErr

enumerator kFLEXIO_A_FORMAT_ES_Busy_MemBusy

enumerator kFLEXIO_A_FORMAT_ES_Batt

enumerator kFLEXIO_A_FORMAT_ES_OvSpd_MemErr_OvTemp_OvFlow

enumerator kFLEXIO_A_FORMAT_ES_STErr_PSErr_MTErr_INCErr

enumerator kFLEXIO_A_FORMAT_ES_FrameErr

enumerator kFLEXIO_A_FORMAT_ES_Anyone

enum _flexio_a_format_baud_rate_bps
FlexIO A_FORMAT baud rate.
Values:

enumerator kFLEXIO_A_FORMAT_2_5MHZ
Baud rate is 2.5Mbps

enumerator kFLEXIO_A_FORMAT_4MHZ
Baud rate is 4Mbps

enumerator kFLEXIO_A_FORMAT_6_67MHZ
Baud rate is 6.67Mbps

enumerator kFLEXIO_A_FORMAT_8MHZ
Baud rate is 8Mbps

enumerator kFLEXIO_A_FORMAT_16MHZ
Baud rate is 16Mbps

enum _flexio_a_format_user_modes
FlexIO A_FORMAT user modes.
Values:

enumerator kFLEXIO_A_FORMAT_USERMODE_ONESHOT
User mode is oneshot

enumerator kFLEXIO_A_FORMAT_USERMODE_SYNC
User mode is sync

enum _flexio_a_format_interrupt_enable
Define FlexIO A-format interrupt mask.
Values:

enumerator kFLEXIO_A_FORMAT_TxDataRegEmptyInterruptEnable
Transmit buffer empty interrupt enable.

enumerator kFLEXIO_A_FORMAT_RxDataRegFullInterruptEnable
Receive buffer full interrupt enable.

enum _flexio_a_format_status_flags
Define FlexIO A-format status mask.
Values:

enumerator kFLEXIO_A_FORMAT_TxDataRegEmptyFlag
Transmit buffer empty flag.

enumerator kFLEXIO_A_FORMAT_RxDataRegFullFlag
Receive buffer full flag.

enumerator kFLEXIO_A_FORMAT_RxOverRunFlag
Receive buffer over run flag.

typedef enum *_flexio_a_format_encoder_status* flexio_a_format_es_t

typedef enum *_flexio_a_format_baud_rate_bps* flexio_a_format_baud_rate_bps_t

FlexIO A_FORMAT baud rate.

typedef enum *_flexio_a_format_user_modes* flexio_a_format_user_modes_t

FlexIO A_FORMAT user modes.

typedef struct *_flexio_a_format_handle* flexio_a_format_handle_t

typedef struct *_flexio_a_format_type* FLEXIO_A_FORMAT_Type

Define FlexIO A_FORMAT access structure typedef.

typedef struct *_flexio_a_format_config* flexio_a_format_config_t

Define FlexIO A_FORMAT user configuration structure.

typedef struct *_flexio_a_format_transfer* flexio_a_format_transfer_t

Define FlexIO A-format transfer structure.

typedef void (*flexio_a_format_transfer_callback_t)(*FLEXIO_A_FORMAT_Type* *base, *flexio_a_format_handle_t* *handle, *status_t* status, void *userData)

FlexIO UART transfer callback function.

static inline void FLEXIO_A_Format_WriteHalfWord(*FLEXIO_A_FORMAT_Type* *base, const uint16_t *buffer)

Writes one half word of data.

Note: This is a non-blocking API, which returns directly after the data is put into the data register. Ensure that the TxEmptyFlag is asserted before calling this API.

Parameters

- base – Pointer to the FLEXIO_A_FORMAT_Type structure.
- buffer – The data bytes to send.

static inline void FLEXIO_A_Format_ReadHalfWord(*FLEXIO_A_FORMAT_Type* *base, uint16_t *buffer)

Reads one half word of data.

Note: This is a non-blocking API, which returns directly after the data is read from the data register. Ensure that the RxFullFlag is asserted before calling this API.

Parameters

- base – Pointer to the FLEXIO_A_FORMAT_Type structure.
- buffer – The buffer to store the received bytes.

void FLEXIO_A_Format_Config_DR_length(*FLEXIO_A_FORMAT_Type* *base, uint32_t nFrames)

The duration of the high level of the RS485 DR Pin is set according to the number of frames.

Parameters

- base – Pointer to the FLEXIO_A_FORMAT_Type structure

- nFrames – The number of frames (Each 16bit of data is one frame)

status_t FLEXIO_A_Format_Init(*FLEXIO_A_FORMAT_Type* *base, const *flexio_a_format_config_t* *userConfig, uint32_t srcClock_Hz)

Ungates the FlexIO clock, resets the FlexIO module, configures the FlexIO A-Format hardware, and configures the FlexIO A-Format with FlexIO A-Format configuration. The configuration structure can be filled by the user, or be set with default values by the *FLEXIO_A_Format_GetDefaultConfig()*.

Example

```
FLEXIO_A_FORMAT_Type base = {
.flexioBase = FLEXIO,
.TxPinIndex = 0,
.RxPinIndex = 1,
.shifterIndex = {0,1},
.timerIndex = {0,1}
};
flexio_a_format_config_t config = {
.enableInDoze = false,
.enableInDebug = true,
.enableFastAccess = false,
.baudRate_bps = 2500000
};
FLEXIO_A_Format_Init(&base, &config, srcClock_Hz);
```

Parameters

- base – Pointer to the FLEXIO_A_FORMAT_Type structure.
- userConfig – Pointer to the flexio_a_format_config_t structure.
- srcClock_Hz – FlexIO source clock in Hz.

Return values

- kStatus_Success – Configuration success.
- kStatus_FLEXIO_A_FORMAT_BaudrateNotSupport – Baudrate is not supported for current clock source frequency.

void FLEXIO_A_Format_Deinit(*FLEXIO_A_FORMAT_Type* *base)

Resets the FlexIO A-Format shifter and timer config.

note After calling this API, call the FLEXIO_A_Format_Init to use the FlexIO A_format module.

Parameters

- base – Pointer to FLEXIO_A_FORMAT_Type structure

void FLEXIO_A_Format_GetDefaultConfig(*flexio_a_format_config_t* *userConfig)

Gets the default configuration to configure the FlexIO A-format. The configuration can be used directly for calling the *FLEXIO_A_Format_Init()*. Example:

```
flexio_a_format_config_t config;
FLEXIO_A_Format_GetDefaultConfig(&userConfig);
```

param userConfig Pointer to the flexio_a_format_config_t structure.

void FLEXIO_A_Format_EnableInterrupts(*FLEXIO_A_FORMAT_Type* *base, uint32_t mask)

Enables the FlexIO A-format interrupt.

This function enables the FlexIO A-format interrupt.

Parameters

- base – Pointer to the FLEXIO_A_FORMAT_Type structure.
- mask – Interrupt source.

void FLEXIO_A_Format_DisableInterrupts(*FLEXIO_A_FORMAT_Type* *base, uint32_t mask)

Disables the FlexIO A-format interrupt.

This function disables the FlexIO A-format interrupt.

Parameters

- base – Pointer to the FLEXIO_A_FORMAT_Type structure.
- mask – Interrupt source.

uint32_t FLEXIO_A_Format_GetStatusFlags(*FLEXIO_A_FORMAT_Type* *base)

Gets the FlexIO A-format status flags.

Parameters

- base – Pointer to the FLEXIO_A_FORMAT_Type structure.

Returns

FlexIO A-format status flags.

void FLEXIO_A_Format_ClearStatusFlags(*FLEXIO_A_FORMAT_Type* *base, uint32_t mask)

Clears the FlexIO A-format status flags.

Parameters

- base – Pointer to the FLEXIO_A_FORMAT_Type structure.
- mask – Status flag. The parameter can be any combination of the following values: arg kFLEXIO_A_FORMAT_TxDataRegEmptyFlag arg kFLEXIO_A_FORMAT_RxDataRegFullFlag arg kFLEXIO_A_FORMAT_RxOverRunFlag

status_t FLEXIO_A_Format_WriteBlocking(*FLEXIO_A_FORMAT_Type* *base, const uint16_t *txData, size_t txSize)

Sends a buffer of data bytes.

note This function blocks using the polling method until all bytes have been sent.

Parameters

- base – Pointer to the FLEXIO_A_FORMAT_Type structure.
- txData – The data bytes to send.
- txSize – The number of data bytes to send.

Return values

- kStatus_FLEXIO_A_FORMAT_Timeout – Transmission timed out and was aborted.
- kStatus_Success – Successfully wrote all data.

status_t FLEXIO_A_Format_ReadBlocking(*FLEXIO_A_FORMAT_Type* *base, uint16_t *rxData, size_t rxSize)

Receives a buffer of bytes.

note This function blocks using the polling method until all bytes have been received.

Parameters

- base – Pointer to the FLEXIO_A_FORMAT_Type structure.
- rxData – The buffer to store the received bytes.

- rxSize – The number of data bytes to be received.

Return values

- kStatus_FLEXIO_A_FORMAT_Timeout – Transmission timed out and was aborted.
- kStatus_Success – Successfully received all data.

status_t FLEXIO_A_Format_TransferCreateHandle(*FLEXIO_A_FORMAT_Type* *base, *flexio_a_format_handle_t* *handle, *flexio_a_format_transfer_callback_t* callback, void *userData)

Initializes the A-format handle.

This function initializes the FlexIO A-format handle, which can be used for other FlexIO A-format transactional APIs. Call this API once to get the initialized handle.

The A-format driver supports the "background" receiving, which means that users can set up a RX ring buffer optionally. Data received is stored into the ring buffer even when the user doesn't call the *FLEXIO_A_Format_TransferReceiveNonBlocking()* API. If there is already data received in the ring buffer, users can get the received data from the ring buffer directly. The ring buffer is disabled if passing NULL as p ringBuffer.

Parameters

- base – to FLEXIO_A_FORMAT_Type structure.
- handle – Pointer to the flexio_a_format_handle_t structure to store the transfer state.
- callback – The callback function.
- userData – The parameter of the callback function.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_OutOfRange – The FlexIO type/handle/ISR table out of range.

void FLEXIO_A_Format_TransferStartRingBuffer(*FLEXIO_A_FORMAT_Type* *base, *flexio_a_format_handle_t* *handle, uint16_t *ringBuffer, size_t ringBufferSize)

Sets up the RX ring buffer.

This function sets up the RX ring buffer to a specific A-format handle.

When the RX ring buffer is used, data received is stored into the ring buffer even when the user doesn't call the A_Format_ReceiveNonBlocking() API. If there is already data received in the ring buffer, users can get the received data from the ring buffer directly.

note When using the RX ring buffer, one byte is reserved for internal use. In other words, if p ringBufferSize is 32, only 31 bytes are used for saving data.

Parameters

- base – Pointer to the FLEXIO_A_FORMAT_Type structure.
- handle – Pointer to the flexio_a_format_handle_t structure to store the transfer state.
- ringBuffer – Start address of ring buffer for background receiving. Pass NULL to disable the ring buffer.
- ringBufferSize – Size of the ring buffer.

void FLEXIO_A_Format_TransferStopRingBuffer(*FLEXIO_A_FORMAT_Type* *base, *flexio_a_format_handle_t* *handle)

Aborts the background transfer and uninstalls the ring buffer.

This function aborts the background transfer and uninstalls the ring buffer.

Parameters

- base – Pointer to the FLEXIO_A_FORMAT_Type structure.
- handle – Pointer to the flexio_a_format_handle_t structure to store the transfer state.

status_t FLEXIO_A_Format_TransferSendNonBlocking(*FLEXIO_A_FORMAT_Type* *base, *flexio_a_format_handle_t* *handle, *flexio_a_format_transfer_t* *xfer)

Transmits a buffer of data using the interrupt method.

This function sends data using an interrupt method. This is a non-blocking function, which returns directly without waiting for all data to be written to the TX register. When all data is written to the TX register in ISR, the FlexIO A-format driver calls the callback function and passes the ref kStatus_FLEXIO_A_FORMAT_TxIdle as status parameter.

note The kStatus_FLEXIO_A_FORMAT_TxIdle is passed to the upper layer when all data is written to the TX register. However, it does not ensure that all data is sent out.

Parameters

- base – Pointer to the FLEXIO_A_FORMAT_Type structure.
- handle – Pointer to the flexio_a_format_handle_t structure to store the transfer state.
- xfer – FlexIO A-format transfer structure. See *flexio_a_format_transfer_t*.

Return values

- kStatus_Success – Successfully starts the data transmission.
- kStatus_A_FORMAT_TxBusy – Previous transmission still not finished, data not written to the TX register.

void FLEXIO_A_Format_TransferAbortSend(*FLEXIO_A_FORMAT_Type* *base, *flexio_a_format_handle_t* *handle)

Aborts the interrupt-driven data transmit.

This function aborts the interrupt-driven data sending. Get the remainHalfwords to find out how many half-words are still not sent out.

Parameters

- base – Pointer to the FLEXIO_A_FORMAT_Type structure.
- handle – Pointer to the flexio_a_format_handle_t structure to store the transfer state.

status_t FLEXIO_A_Format_TransferGetSendCount(*FLEXIO_A_FORMAT_Type* *base, *flexio_a_format_handle_t* *handle, size_t *count)

Gets the number of half-words sent.

This function gets the number of half-words sent driven by interrupt.

Parameters

- base – Pointer to the FLEXIO_A_FORMAT_Type structure.
- handle – Pointer to the flexio_a_format_handle_t structure to store the transfer state.

- count – Number of half-words sent so far by the non-blocking transaction.

Return values

- kStatus_NoTransferInProgress – transfer has finished or no transfer in progress.
- kStatus_Success – Successfully return the count.

status_t FLEXIO_A_Format_TransferReceiveNonBlocking(*FLEXIO_A_FORMAT_Type* *base, *flexio_a_format_handle_t* *handle, *flexio_a_format_transfer_t* *xfer, size_t *receivedHalfWords)

Receives a buffer of data using the interrupt method.

This function receives data using the interrupt method. This is a non-blocking function, which returns without waiting for all data to be received. If the RX ring buffer is used and not empty, the data in ring buffer is copied and the parameter p receivedHalfWords shows how many half-words are copied from the ring buffer. After copying, if the data in ring buffer is not enough to read, the receive request is saved by the A-format driver. When new data arrives, the receive request is serviced first. When all data is received, the A-format driver notifies the upper layer through a callback function and passes the status parameter ref kStatus_A_FORMAT_RxIdle. For example, if the upper layer needs 10 half-words but there are only 5 half-words in the ring buffer, the 5 half-words are copied to xfer->data. This function returns with the parameter p receivedHalfWords set to 5. For the last 5 half-words, newly arrived data is saved from the xfer->data[5]. When 5 half-words are received, the A-format driver notifies upper layer. If the RX ring buffer is not enabled, this function enables the RX and RX interrupt to receive data to xfer->data. When all data is received, the upper layer is notified.

Parameters

- base – Pointer to the FLEXIO_A_FORMAT_Type structure.
- handle – Pointer to the flexio_a_format_handle_t structure to store the transfer state.
- xfer – A-format transfer structure. See *flexio_a_format_transfer_t*.
- receivedHalfWords – Half-words received from the ring buffer directly.

Return values

- kStatus_Success – Successfully queue the transfer into the transmit queue.
- kStatus_FLEXIO_A_FORMAT_RxBusy – Previous receive request is not finished.

void FLEXIO_A_Format_TransferAbortReceive(*FLEXIO_A_FORMAT_Type* *base, *flexio_a_format_handle_t* *handle)

Aborts the receive data which was using IRQ.

This function aborts the receive data which was using IRQ.

Parameters

- base – Pointer to the FLEXIO_A_FORMAT_Type structure.
- handle – Pointer to the flexio_a_format_handle_t structure to store the transfer state.

status_t FLEXIO_A_Format_TransferGetReceiveCount(*FLEXIO_A_FORMAT_Type* *base, *flexio_a_format_handle_t* *handle, size_t *count)

Gets the number of half-words received.

This function gets the number of half-words received driven by interrupt.

Parameters

- base – Pointer to the FLEXIO_A_FORMAT_Type structure.
- handle – Pointer to the flexio_a_format_handle_t structure to store the transfer state.
- count – Number of half-words received so far by the non-blocking transaction.

Return values

- kStatus_NoTransferInProgress – transfer has finished or no transfer in progress.
- kStatus_Success – Successfully return the count.

void FLEXIO_A_Format_TransferHandleIRQ(void *uartType, void *uartHandle)

FlexIO A-format IRQ handler function.

This function processes the FlexIO A-format transmit and receives the IRQ request.

Parameters

- uartType – Pointer to the FLEXIO_A_FORMAT_Type structure.
- uartHandle – Pointer to the flexio_a_format_handle_t structure to store the transfer state.

void FLEXIO_A_Format_FlushShifters(*FLEXIO_A_FORMAT_Type* *base)

brief Flush tx/rx shifters.

param base Pointer to the FLEXIO_A_FORMAT_Type structure.

A_FORMAT_SYNC_CODE_CMD

The command data frame sync code of A-format.

A_FORMAT_SYNC_CODE_IF

The encoder information field sync code of A-format.

A_FORMAT_FRAME_CODE_CDF

A-format CDF frame code.

A_FORMAT_FRAME_CODE_MDF0

A-format MDF frame code.

A_FORMAT_FRAME_CODE_MDF1

A_FORMAT_FRAME_CODE_MDF2

A_FORMAT_CDF(x)

A-format command code.

A_FORMAT_REQ_IT_ABS_FULL_40BIT

brief Give the command code an alias

IT: Individual Transmission MT: Multiple Transmission

A_FORMAT_REQ_IT_ABS_LOWER_24BIT

A_FORMAT_REQ_IT_ABS_UPPER_24BIT

A_FORMAT_REQ_IT_ENCODER_STAT

A_FORMAT_REQ_MT_ABS_FULL_40BIT

A_FORMAT_REQ_MT_ABS_LOWER_24BIT

A_FORMAT_REQ_MT_ABS_UPPER_24BIT

A_FORMAT_REQ_MT_ENCODER_STAT

A_FORMAT_REQ_IT_CLEAR_STAT_FLAG

A_FORMAT_REQ_IT_CLEAR_MULTI_TURN

A_FORMAT_REQ_IT_CLEAR_STAT_MULTI

A_FORMAT_REQ_IT_SET_ENCODER_ADDR1

A_FORMAT_REQ_IT_PRESET_SINGLE_TURN_0

A_FORMAT_REQ_IT_MEMORY_READ

A_FORMAT_REQ_IT_MEMORY_WRITE

A_FORMAT_REQ_IT_TEMPERATURE_10BIT

A_FORMAT_REQ_IT_ID_CODE_READ1

A_FORMAT_REQ_IT_ID_CODE_READ2

A_FORMAT_REQ_IT_ID_CODE_WRITE1

A_FORMAT_REQ_IT_ID_CODE_WRITE2

A_FORMAT_REQ_IT_SET_ENCODER_ADDR2

A_FORMAT_REQ_IT_ABS_LOWER_17BIT

A_FORMAT_REQ_MT_ABS_LOWER_17BIT

A_FORMAT_REQ_IT_ABS_LOWER_24BIT_STAT

A_FORMAT_REQ_MT_ABS_LOWER_24BIT_STAT

A_FORMAT_REQ_IT_ABS_LOWER_24BIT_TEMP

A_FORMAT_REQ_MT_ABS_LOWER_24BIT_TEMP

A_FORMAT_CRC_POLY_COMMAND_DATA
: The command data CRC polynomial of A-format.

A_FORMAT_CRC_POLY_ENCODER_DATA
: The encoder data CRC polynomial of A-format.

A_FORMAT_CDF_MASK_SYNC_CODE
: The mask of the CDF sync code.

A_FORMAT_CDF_MASK_FRAME_CODE
: The mask of the CDF frame code.

A_FORMAT_CDF_MASK_ENCODER_ADDR
: The mask of the CDF encoder address.

A_FORMAT_CDF_MASK_COMMAND_CODE
: The mask of the CDF command code.

A_FORMAT_CDF_MASK_CRC_CODE
: The mask of the CDF CRC code.

A_FORMAT_MDF_MASK_SYNC_CODE
: The mask of the MDF sync code.

A_FORMAT_MDF_MASK_FRAME_CODE
: The mask of the MDF frame code.

A_FORMAT_MDF_MASK_DATA_BIT
: The mask of the MDF data bit.

A_FORMAT_MDF_MASK_CRC_CODE
: The mask of the MDF CRC code.

A_FORMAT_IF_MASK_ENCODER_ADDR
: The mask of the IF encoder address.

A_FORMAT_IF_MASK_COMMAND_CODE
: The mask of the IF command code.

A_FORMAT_IF_MASK_ENCODER_STAT
: The mask of the IF encoder status.

A_FORMAT_CDF_SHIFT_SYNC_CODE(x)
: Shift the sync code for command data frame.

A_FORMAT_CDF_SHIFT_FRAME_CODE(x)
Shift the frame code for command data frame.

A_FORMAT_CDF_SHIFT_ENCODER_ADDR(x)
Shift the encoder address for command data frame.

A_FORMAT_CDF_SHIFT_COMMAND_CODE(x)
Shift the command code for command data frame.

A_FORMAT_CDF_SHIFT_CRC_CODE(x)
Shift the CRC code for command data frame.

A_FORMAT_MDF_SHIFT_SYNC_CODE(x)
Shift the sync code for memory data frame.

A_FORMAT_MDF_SHIFT_FRAME_CODE(x)
Shift the frame code for memory data frame.

A_FORMAT_MDF_SHIFT_DATA_BIT(x)
Shift the data bit for memory data frame.

A_FORMAT_MDF_SHIFT_CRC_CODE(x)
Shift the CRC code for memory data frame.

A_FORMAT_PACK_CDF(EA, CC, CRC)
Pack the command data frame.

A_FORMAT_PACK_MDF(FC, DA, CRC)
Pack the memory data frame.

A_FORMAT_GET_ENC_ADDR_CDF(x)
Get encoder address from the CDF frame.

A_FORMAT_GET_CMD_CODE_CDF(x)
Get command code from the CDF frame.

A_FORMAT_CRC_RANGE_IN_CDF
The mask of CRC-applied range in CDF frame.

A_FORMAT_GET_CRC_DATA_CDF(x)
Get CRC data from the CDF frame.

A_FORMAT_GET_CRC_CODE_CDF(x)
Get CRC code from the CDF frame.

A_FORMAT_SET_CRC_CODE_CDF(cdf, crc)
Set CRC code to the CDF frame.

A_FORMAT_CRC_RANGE_IN_MDF
The mask of CRC-applied range in MDF frame.

A_FORMAT_GET_CRC_DATA_MDF(x)
Get CRC data from the MDF frame.

A_FORMAT_SET_CRC_CODE_MDF(mdf, crc)
Set CRC code to the MDF frame.

A_FORMAT_GET_ENC_ADDR_IF(x)
Get encoder address from the IF frame.

A_FORMAT_GET_CMD_CODE_IF(x)
Get command code from the IF frame.

A_FORMAT_GET_ENC_STAT_IF(x)
Get encoder status from the IF frame.

ENCODER_ADDRESS_IT(x)

ENCODER_ADDRESS_MT(x)

ENCODER_ADDRESS_IS_MT(x)

ENCODER_ADDRESS(x)

HALFWORD_NUM(x)

GET_TEMPERATURE_IS_BELOW_ZERO(x)

GET_TEMPERATURE_DATA(x)

GET_TEMPERATURE_VALUE(x)

GET_ENCODER_ID(x)

A_FORMAT_TIMER_TX_INDEX

A_FORMAT_TIMER_TX_CLOCK_INDEX

A_FORMAT_TIMER_RX_INDEX

A_FORMAT_TIMER_RX_CLOCK_INDEX

A_FORMAT_TIMER_DR_INDEX

FSL_FLEXIO_A_FORMAT_DRIVER_VERSION
FlexIO A_Format driver version.

A_FORMAT_RETRY_TIMES
Retry times for waiting flag.

A_FORMAT_ENCODER_MAX_NUM
Maximum number of encoders on an A-format bus.

A_FORMAT_BITS_PER_FRAME_DATA
The number of bits per frame without start and stop bits.

A_FORMAT_BITS_PER_FRAME_WHOLE
The number of bits per frame with start and stop bits.

A_FORMAT_TIMER_COMPARE_VALUE(cmp)
Calculate the value of the FlexIO timer compare register.

FLEXIO_Type *flexioBase
FlexIO base pointer.

flexio_a_format_handle_t *hanlde

uint16_t timerDiv
: srcClock_Hz / baudRate_bps

uint16_t TxDR_Offset
: The offset between Tx and DR pins

uint16_t interval
: Interval between frames

uint8_t TxPinIndex
: Pin select for A_FORMAT_Tx.

uint8_t RxPinIndex
: Pin select for A_FORMAT_Rx.

uint8_t DRPinIndex
: Pin select for A_FORMAT_DR.

uint8_t shifterIndex[2]
: Shifter index used in FlexIO A_FORMAT.

uint8_t timerIndex[5]
: Timer index used in FlexIO A_FORMAT.

uint8_t triggerIn
: Trigger signal for sync mode.

bool enableA_Format
: Enable/disable FlexIO A_FORMAT TX & RX.

bool enableInDoze
: Enable/disable FlexIO operation in doze mode

bool enableInDebug
: Enable/disable FlexIO operation in debug mode

bool enableFastAccess
: Enable/disable fast access to FlexIO registers, fast access requires the FlexIO clock to be at least twice the frequency of the bus clock.

flexio_a_format_baud_rate_bps_t baudRate_bps
: Baud rate in bps.

uint8_t userMode

uint16_t *data
: The buffer of data to be transfer.

uint16_t *rxData
The buffer to receive data.

const uint16_t *txData
The buffer of data to be sent.

union __flexio_a_format_transfer

size_t dataSize
Transfer size

const uint16_t *volatile txData
Address of remaining data to send.

volatile size_t txDataSize
Size of the remaining data to send.

uint16_t *volatile rxData
Address of remaining data to receive.

volatile size_t rxDataSize
Size of the remaining data to receive.

size_t txDataSizeAll
Total bytes to be sent.

size_t rxDataSizeAll
Total bytes to be received.

uint16_t *rxRingBuffer
Start address of the receiver ring buffer.

size_t rxRingBufferSize
Size of the ring buffer.

volatile uint16_t rxRingBufferHead
Index for the driver to store received data into ring buffer.

volatile uint16_t rxRingBufferTail
Index for the user to get data from the ring buffer.

flexio_a_format_transfer_callback_t callback
Callback function.

void *userData
A-format callback function parameter.

volatile uint8_t txState
TX transfer state.

volatile uint8_t rxState
RX transfer state

struct _flexio_a_format_type
#include <fsl_flexio_a-format.h> Define FlexIO A_FORMAT access structure typedef.

struct _flexio_a_format_config
#include <fsl_flexio_a-format.h> Define FlexIO A_FORMAT user configuration structure.

struct _flexio_a_format_transfer
#include <fsl_flexio_a-format.h> Define FlexIO A-format transfer structure.

struct _flexio_a_format_handle
#include <fsl_flexio_a-format.h> Define FLEXIO A-format handle structure.

union ___unnamed84___

Public Members

uint16_t *data
The buffer of data to be transfer.

uint16_t *rxData
The buffer to receive data.

const uint16_t *txData
The buffer of data to be sent.

2.19 FlexIO Camera Driver

void FLEXIO_CAMERA_Init(*FLEXIO_CAMERA_Type* *base, const *flexio_camera_config_t* *config)
Ungates the FlexIO clock, resets the FlexIO module, and configures the FlexIO Camera.

Parameters

- base – Pointer to FLEXIO_CAMERA_Type structure
- config – Pointer to flexio_camera_config_t structure

void FLEXIO_CAMERA_Deinit(*FLEXIO_CAMERA_Type* *base)
Resets the FLEXIO_CAMERA shifer and timer config.

Note: After calling this API, call FLEXO_CAMERA_Init to use the FlexIO Camera module.

Parameters

- base – Pointer to FLEXIO_CAMERA_Type structure

void FLEXIO_CAMERA_GetDefaultConfig(*flexio_camera_config_t* *config)

Gets the default configuration to configure the FlexIO Camera. The configuration can be used directly for calling the *FLEXIO_CAMERA_Init()*. Example:

```
flexio_camera_config_t config;
FLEXIO_CAMERA_GetDefaultConfig(&userConfig);
```

Parameters

- config – Pointer to the flexio_camera_config_t structure

static inline void FLEXIO_CAMERA_Enable(*FLEXIO_CAMERA_Type* *base, bool enable)

Enables/disables the FlexIO Camera module operation.

Parameters

- base – Pointer to the FLEXIO_CAMERA_Type
- enable – True to enable, false does not have any effect.

uint32_t FLEXIO_CAMERA_GetStatusFlags(*FLEXIO_CAMERA_Type* *base)

Gets the FlexIO Camera status flags.

Parameters

- base – Pointer to FLEXIO_CAMERA_Type structure

Returns

FlexIO shifter status flags

- FLEXIO_SHIFTSTAT_SSF_MASK
- 0

void FLEXIO_CAMERA_ClearStatusFlags(*FLEXIO_CAMERA_Type* *base, uint32_t mask)

Clears the receive buffer full flag manually.

Parameters

- base – Pointer to the device.
- mask – status flag The parameter can be any combination of the following values:
  - kFLEXIO_CAMERA_RxDataRegFullFlag
  - kFLEXIO_CAMERA_RxErrorFlag

void FLEXIO_CAMERA_EnableInterrupt(*FLEXIO_CAMERA_Type* *base)

Switches on the interrupt for receive buffer full event.

Parameters

- base – Pointer to the device.

void FLEXIO_CAMERA_DisableInterrupt(*FLEXIO_CAMERA_Type* *base)

Switches off the interrupt for receive buffer full event.

Parameters

- base – Pointer to the device.

static inline void FLEXIO_CAMERA_EnableRxDMA(*FLEXIO_CAMERA_Type* *base, bool enable)

Enables/disables the FlexIO Camera receive DMA.

The FlexIO Camera mode can't work without the DMA or eDMA support, Usually, it needs at least two DMA or eDMA channels, one for transferring data from Camera, such as 0V7670 to FlexIO buffer, another is for transferring data from FlexIO buffer to LCD.

Parameters

- base – Pointer to FLEXIO_CAMERA_Type structure
- enable – True to enable, false to disable.

static inline uint32_t FLEXIO_CAMERA_GetRxBufferAddress(*FLEXIO_CAMERA_Type* *base)

Gets the data from the receive buffer.

Parameters

- base – Pointer to the device.

Returns

data Pointer to the buffer that keeps the data with count of base->shifterCount .

FSL_FLEXIO_CAMERA_DRIVER_VERSION

FlexIO Camera driver version.

Error codes for the Camera driver.

Values:

enumerator kStatus_FLEXIO_CAMERA_RxBusy

Receiver is busy.

enumerator kStatus_FLEXIO_CAMERA_RxIdle

Camera receiver is idle.

enum _flexio_camera_status_flags

Define FlexIO Camera status mask.

Values:

enumerator kFLEXIO_CAMERA_RxDataRegFullFlag

Receive buffer full flag.

enumerator kFLEXIO_CAMERA_RxErrorFlag

Receive buffer error flag.

typedef struct *_flexio_camera_type* FLEXIO_CAMERA_Type

Define structure of configuring the FlexIO Camera device.

typedef struct *_flexio_camera_config* flexio_camera_config_t

Define FlexIO Camera user configuration structure.

typedef struct *_flexio_camera_transfer* flexio_camera_transfer_t

Define FlexIO Camera transfer structure.

FLEXIO_CAMERA_PARALLEL_DATA_WIDTH

Define the Camera CPI interface is constantly 8-bit width.

struct _flexio_camera_type

#include <fsl_flexio_camera.h> Define structure of configuring the FlexIO Camera device.

Public Members

FLEXIO_Type *flexioBase

FlexIO module base address.

uint32_t datPinStartIdx

First data pin (D0) index for flexio_camera. Then the successive following FLEXIO_CAMERA_DATA_WIDTH-1 pins are used as D1-D7.

uint32_t pclkPinIdx

Pixel clock pin (PCLK) index for flexio_camera.

uint32_t hrefPinIdx

Horizontal sync pin (HREF) index for flexio_camera.

uint8_t shifterStartIdx

First shifter index used for flexio_camera data FIFO.

uint32_t shifterCount

The count of shifters that are used as flexio_camera data FIFO.

uint32_t timerIdx

Timer index used for flexio_camera in FlexIO.

struct _flexio_camera_config

#include <fsl_flexio_camera.h> Define FlexIO Camera user configuration structure.

Public Members

bool enablecamera

Enable/disable FlexIO Camera TX & RX.

bool enableInDoze

Enable/disable FlexIO operation in doze mode

bool enableInDebug

Enable/disable FlexIO operation in debug mode

bool enableFastAccess

Enable/disable fast access to FlexIO registers, fast access requires the FlexIO clock to be at least twice the frequency of the bus clock.

struct _flexio_camera_transfer

#include <fsl_flexio_camera.h> Define FlexIO Camera transfer structure.

Public Members

uint32_t dataAddress

Transfer buffer

uint32_t dataNum

Transfer num

2.20 FlexIO Driver

void FLEXIO_GetDefaultConfig(*flexio_config_t* *userConfig)

Gets the default configuration to configure the FlexIO module. The configuration can used directly to call the FLEXIO_Configure().

Example:

```
flexio_config_t config;
FLEXIO_GetDefaultConfig(&config);
```

Parameters

- userConfig – pointer to flexio_config_t structure

void FLEXIO_Init(FLEXIO_Type *base, const *flexio_config_t* *userConfig)

Configures the FlexIO with a FlexIO configuration. The configuration structure can be filled by the user or be set with default values by *FLEXIO_GetDefaultConfig()*.

Example

```
flexio_config_t config = {
.enableFlexio = true,
.enableInDoze = false,
.enableInDebug = true,
.enableFastAccess = false
};
FLEXIO_Configure(base, &config);
```

Parameters

- base – FlexIO peripheral base address
- userConfig – pointer to flexio_config_t structure

void FLEXIO_Deinit(FLEXIO_Type *base)

Gates the FlexIO clock. Call this API to stop the FlexIO clock.

Note: After calling this API, call the FLEXO_Init to use the FlexIO module.

Parameters

- base – FlexIO peripheral base address

uint32_t FLEXIO_GetInstance(FLEXIO_Type *base)

Get instance number for FLEXIO module.

Parameters

- base – FLEXIO peripheral base address.

void FLEXIO_Reset(FLEXIO_Type *base)

Resets the FlexIO module.

Parameters

- base – FlexIO peripheral base address

static inline void FLEXIO_Enable(FLEXIO_Type *base, bool enable)

Enables the FlexIO module operation.

Parameters

- base – FlexIO peripheral base address
- enable – true to enable, false to disable.

static inline uint32_t FLEXIO_ReadPinInput(FLEXIO_Type *base)

Reads the input data on each of the FlexIO pins.

Parameters

- base – FlexIO peripheral base address

Returns

FlexIO pin input data

static inline uint8_t FLEXIO_GetShifterState(FLEXIO_Type *base)

Gets the current state pointer for state mode use.

Parameters

- base – FlexIO peripheral base address

Returns

current State pointer

void FLEXIO_SetShifterConfig(FLEXIO_Type *base, uint8_t index, const *flexio_shifter_config_t* *shifterConfig)

Configures the shifter with the shifter configuration. The configuration structure covers both the SHIFTCTL and SHIFTCFG registers. To configure the shifter to the proper mode, select which timer controls the shifter to shift, whether to generate start bit/stop bit, and the polarity of start bit and stop bit.

Example

```
flexio_shifter_config_t config = {
.timerSelect = 0,
.timerPolarity = kFLEXIO_ShifterTimerPolarityOnPositive,
```

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```
.pinConfig = kFLEXIO_PinConfigOpenDrainOrBidirection,
.pinPolarity = kFLEXIO_PinActiveLow,
.shifterMode = kFLEXIO_ShifterModeTransmit,
.inputSource = kFLEXIO_ShifterInputFromPin,
.shifterStop = kFLEXIO_ShifterStopBitHigh,
.shifterStart = kFLEXIO_ShifterStartBitLow
};
FLEXIO_SetShifterConfig(base, &config);
```

Parameters

- base – FlexIO peripheral base address
- index – Shifter index
- shifterConfig – Pointer to flexio_shifter_config_t structure

void FLEXIO_SetTimerConfig(FLEXIO_Type *base, uint8_t index, const *flexio_timer_config_t* *timerConfig)

Configures the timer with the timer configuration. The configuration structure covers both the TIMCTL and TIMCFG registers. To configure the timer to the proper mode, select trigger source for timer and the timer pin output and the timing for timer.

Example

```
flexio_timer_config_t config = {
.triggerSelect = FLEXIO_TIMER_TRIGGER_SEL_SHIFTnSTAT(0),
.triggerPolarity = kFLEXIO_TimerTriggerPolarityActiveLow,
.triggerSource = kFLEXIO_TimerTriggerSourceInternal,
.pinConfig = kFLEXIO_PinConfigOpenDrainOrBidirection,
.pinSelect = 0,
.pinPolarity = kFLEXIO_PinActiveHigh,
.timerMode = kFLEXIO_TimerModeDual8BitBaudBit,
.timerOutput = kFLEXIO_TimerOutputZeroNotAffectedByReset,
.timerDecrement = kFLEXIO_TimerDecSrcOnFlexIOClockShiftTimerOutput,
.timerReset = kFLEXIO_TimerResetOnTimerPinEqualToTimerOutput,
.timerDisable = kFLEXIO_TimerDisableOnTimerCompare,
.timerEnable = kFLEXIO_TimerEnableOnTriggerHigh,
.timerStop = kFLEXIO_TimerStopBitEnableOnTimerDisable,
.timerStart = kFLEXIO_TimerStartBitEnabled
};
FLEXIO_SetTimerConfig(base, &config);
```

Parameters

- base – FlexIO peripheral base address
- index – Timer index
- timerConfig – Pointer to the flexio_timer_config_t structure

static inline void FLEXIO_SetClockMode(FLEXIO_Type *base, uint8_t index, *flexio_timer_decrement_source_t* clocksource)

This function set the value of the prescaler on flexio channels.

Parameters

- base – Pointer to the FlexIO simulated peripheral type.
- index – Timer index
- clocksource – Set clock value

static inline void FLEXIO_EnableShifterStatusInterrupts(FLEXIO_Type *base, uint32_t mask)

Enables the shifter status interrupt. The interrupt generates when the corresponding SSF is set.

Note: For multiple shifter status interrupt enable, for example, two shifter status enable, can calculate the mask by using ((1 « shifter index0) | (1 « shifter index1))

Parameters

- base – FlexIO peripheral base address
- mask – The shifter status mask which can be calculated by (1 « shifter index)

static inline void FLEXIO_DisableShifterStatusInterrupts(FLEXIO_Type *base, uint32_t mask)

Disables the shifter status interrupt. The interrupt won't generate when the corresponding SSF is set.

Note: For multiple shifter status interrupt enable, for example, two shifter status enable, can calculate the mask by using ((1 « shifter index0) | (1 « shifter index1))

Parameters

- base – FlexIO peripheral base address
- mask – The shifter status mask which can be calculated by (1 « shifter index)

static inline void FLEXIO_EnableShifterErrorInterrupts(FLEXIO_Type *base, uint32_t mask)

Enables the shifter error interrupt. The interrupt generates when the corresponding SEF is set.

Note: For multiple shifter error interrupt enable, for example, two shifter error enable, can calculate the mask by using ((1 « shifter index0) | (1 « shifter index1))

Parameters

- base – FlexIO peripheral base address
- mask – The shifter error mask which can be calculated by (1 « shifter index)

static inline void FLEXIO_DisableShifterErrorInterrupts(FLEXIO_Type *base, uint32_t mask)

Disables the shifter error interrupt. The interrupt won't generate when the corresponding SEF is set.

Note: For multiple shifter error interrupt enable, for example, two shifter error enable, can calculate the mask by using ((1 « shifter index0) | (1 « shifter index1))

Parameters

- base – FlexIO peripheral base address
- mask – The shifter error mask which can be calculated by (1 « shifter index)

static inline void FLEXIO_EnableTimerStatusInterrupts(FLEXIO_Type *base, uint32_t mask)

Enables the timer status interrupt. The interrupt generates when the corresponding SSF is set.

Note: For multiple timer status interrupt enable, for example, two timer status enable, can calculate the mask by using ((1 « timer index0) | (1 « timer index1))

Parameters

- base – FlexIO peripheral base address
- mask – The timer status mask which can be calculated by (1 « timer index)

static inline void FLEXIO_DisableTimerStatusInterrupts(FLEXIO_Type *base, uint32_t mask)

Disables the timer status interrupt. The interrupt won't generate when the corresponding SSF is set.

Note: For multiple timer status interrupt enable, for example, two timer status enable, can calculate the mask by using ((1 « timer index0) | (1 « timer index1))

Parameters

- base – FlexIO peripheral base address
- mask – The timer status mask which can be calculated by (1 « timer index)

static inline uint32_t FLEXIO_GetShifterStatusFlags(FLEXIO_Type *base)

Gets the shifter status flags.

Parameters

- base – FlexIO peripheral base address

Returns

Shifter status flags

static inline void FLEXIO_ClearShifterStatusFlags(FLEXIO_Type *base, uint32_t mask)

Clears the shifter status flags.

Note: For clearing multiple shifter status flags, for example, two shifter status flags, can calculate the mask by using ((1 « shifter index0) | (1 « shifter index1))

Parameters

- base – FlexIO peripheral base address
- mask – The shifter status mask which can be calculated by (1 « shifter index)

static inline uint32_t FLEXIO_GetShifterErrorFlags(FLEXIO_Type *base)

Gets the shifter error flags.

Parameters

- base – FlexIO peripheral base address

Returns

Shifter error flags

static inline void FLEXIO_ClearShifterErrorFlags(FLEXIO_Type *base, uint32_t mask)

Clears the shifter error flags.

Note: For clearing multiple shifter error flags, for example, two shifter error flags, can calculate the mask by using ((1 « shifter index0) | (1 « shifter index1))

Parameters

- base – FlexIO peripheral base address
- mask – The shifter error mask which can be calculated by (1 « shifter index)

static inline uint32_t FLEXIO_GetTimerStatusFlags(FLEXIO_Type *base)

Gets the timer status flags.

Parameters

- base – FlexIO peripheral base address

Returns

Timer status flags

static inline void FLEXIO_ClearTimerStatusFlags(FLEXIO_Type *base, uint32_t mask)

Clears the timer status flags.

Note: For clearing multiple timer status flags, for example, two timer status flags, can calculate the mask by using ((1 « timer index0) | (1 « timer index1))

Parameters

- base – FlexIO peripheral base address
- mask – The timer status mask which can be calculated by (1 « timer index)

static inline void FLEXIO_EnableShifterStatusDMA(FLEXIO_Type *base, uint32_t mask, bool enable)

Enables/disables the shifter status DMA. The DMA request generates when the corresponding SSF is set.

Note: For multiple shifter status DMA enables, for example, calculate the mask by using ((1 « shifter index0) | (1 « shifter index1))

Parameters

- base – FlexIO peripheral base address
- mask – The shifter status mask which can be calculated by (1 « shifter index)
- enable – True to enable, false to disable.

uint32_t FLEXIO_GetShifterBufferAddress(FLEXIO_Type *base, *flexio_shifter_buffer_type_t* type, uint8_t index)

Gets the shifter buffer address for the DMA transfer usage.

Parameters

- base – FlexIO peripheral base address

- type – Shifter type of flexio_shifter_buffer_type_t
- index – Shifter index

Returns
Corresponding shifter buffer index

status_t FLEXIO_RegisterHandleIRQ(void *base, void *handle, *flexio_isr_t* isr)
Registers the handle and the interrupt handler for the FlexIO-simulated peripheral.

Parameters

- base – Pointer to the FlexIO simulated peripheral type.
- handle – Pointer to the handler for FlexIO simulated peripheral.
- isr – FlexIO simulated peripheral interrupt handler.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_OutOfRange – The FlexIO type/handle/ISR table out of range.

status_t FLEXIO_UnregisterHandleIRQ(void *base)
Unregisters the handle and the interrupt handler for the FlexIO-simulated peripheral.

Parameters

- base – Pointer to the FlexIO simulated peripheral type.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_OutOfRange – The FlexIO type/handle/ISR table out of range.

static inline void FLEXIO_ClearPortOutput(FLEXIO_Type *base, uint32_t mask)
Sets the output level of the multiple FLEXIO pins to the logic 0.

Parameters

- base – FlexIO peripheral base address
- mask – FLEXIO pin number mask

static inline void FLEXIO_SetPortOutput(FLEXIO_Type *base, uint32_t mask)
Sets the output level of the multiple FLEXIO pins to the logic 1.

Parameters

- base – FlexIO peripheral base address
- mask – FLEXIO pin number mask

static inline void FLEXIO_TogglePortOutput(FLEXIO_Type *base, uint32_t mask)
Reverses the current output logic of the multiple FLEXIO pins.

Parameters

- base – FlexIO peripheral base address
- mask – FLEXIO pin number mask

static inline void FLEXIO_PinWrite(FLEXIO_Type *base, uint32_t pin, uint8_t output)
Sets the output level of the FLEXIO pins to the logic 1 or 0.

Parameters

- base – FlexIO peripheral base address
- pin – FLEXIO pin number.

- output – FLEXIO pin output logic level.
  - 0: corresponding pin output low-logic level.
  - 1: corresponding pin output high-logic level.

static inline void FLEXIO_EnablePinOutput(FLEXIO_Type *base, uint32_t pin)

Enables the FLEXIO output pin function.

Parameters

- base – FlexIO peripheral base address
- pin – FLEXIO pin number.

static inline uint32_t FLEXIO_PinRead(FLEXIO_Type *base, uint32_t pin)

Reads the current input value of the FLEXIO pin.

Parameters

- base – FlexIO peripheral base address
- pin – FLEXIO pin number.

Return values

FLEXIO – port input value

- 0: corresponding pin input low-logic level.
- 1: corresponding pin input high-logic level.

static inline uint32_t FLEXIO_GetPinStatus(FLEXIO_Type *base, uint32_t pin)

Gets the FLEXIO input pin status.

Parameters

- base – FlexIO peripheral base address
- pin – FLEXIO pin number.

Return values

FLEXIO – port input status

- 0: corresponding pin input capture no status.
- 1: corresponding pin input capture rising or falling edge.

static inline void FLEXIO_SetPinLevel(FLEXIO_Type *base, uint8_t pin, bool level)

Sets the FLEXIO output pin level.

Parameters

- base – FlexIO peripheral base address
- pin – FlexIO pin number.
- level – FlexIO output pin level to set, can be either 0 or 1.

static inline bool FLEXIO_GetPinOverride(const FLEXIO_Type *const base, uint8_t pin)

Gets the enabled status of a FLEXIO output pin.

Parameters

- base – FlexIO peripheral base address
- pin – FlexIO pin number.

Return values

FlexIO – port enabled status

- 0: corresponding output pin is in disabled state.
- 1: corresponding output pin is in enabled state.

static inline void FLEXIO_ConfigPinOverride(FLEXIO_Type *base, uint8_t pin, bool enabled)

Enables or disables a FLEXIO output pin.

Parameters

- base – FlexIO peripheral base address
- pin – Flexio pin number.
- enabled – Enable or disable the FlexIO pin.

static inline void FLEXIO_ClearPortStatus(FLEXIO_Type *base, uint32_t mask)

Clears the multiple FLEXIO input pins status.

Parameters

- base – FlexIO peripheral base address
- mask – FLEXIO pin number mask

FSL_FLEXIO_DRIVER_VERSION

FlexIO driver version.

enum _flexio_timer_trigger_polarity

Define time of timer trigger polarity.

Values:

enumerator kFLEXIO_TimerTriggerPolarityActiveHigh

Active high.

enumerator kFLEXIO_TimerTriggerPolarityActiveLow

Active low.

enum _flexio_timer_trigger_source

Define type of timer trigger source.

Values:

enumerator kFLEXIO_TimerTriggerSourceExternal

External trigger selected.

enumerator kFLEXIO_TimerTriggerSourceInternal

Internal trigger selected.

enum _flexio_pin_config

Define type of timer/shifter pin configuration.

Values:

enumerator kFLEXIO_PinConfigOutputDisabled

Pin output disabled.

enumerator kFLEXIO_PinConfigOpenDrainOrBidirection

Pin open drain or bidirectional output enable.

enumerator kFLEXIO_PinConfigBidirectionOutputData
Pin bidirectional output data.

enumerator kFLEXIO_PinConfigOutput
Pin output.

enum _flexio_pin_polarity
Definition of pin polarity.
Values:

enumerator kFLEXIO_PinActiveHigh
Active high.

enumerator kFLEXIO_PinActiveLow
Active low.

enum _flexio_timer_mode
Define type of timer work mode.
Values:

enumerator kFLEXIO_TimerModeDisabled
Timer Disabled.

enumerator kFLEXIO_TimerModeDual8BitBaudBit
Dual 8-bit counters baud/bit mode.

enumerator kFLEXIO_TimerModeDual8BitPWM
Dual 8-bit counters PWM mode.

enumerator kFLEXIO_TimerModeSingle16Bit
Single 16-bit counter mode.

enumerator kFLEXIO_TimerModeDual8BitPWMLow
Dual 8-bit counters PWM Low mode.

enum _flexio_timer_output
Define type of timer initial output or timer reset condition.
Values:

enumerator kFLEXIO_TimerOutputOneNotAffectedByReset
Logic one when enabled and is not affected by timer reset.

enumerator kFLEXIO_TimerOutputZeroNotAffectedByReset
Logic zero when enabled and is not affected by timer reset.

enumerator kFLEXIO_TimerOutputOneAffectedByReset
Logic one when enabled and on timer reset.

enumerator kFLEXIO_TimerOutputZeroAffectedByReset
Logic zero when enabled and on timer reset.

enum _flexio_timer_decrement_source
Define type of timer decrement.
Values:

enumerator kFLEXIO_TimerDecSrcOnFlexIOClockShiftTimerOutput
Decrement counter on FlexIO clock, Shift clock equals Timer output.

enumerator kFLEXIO_TimerDecSrcOnTriggerInputShiftTimerOutput
Decrement counter on Trigger input (both edges), Shift clock equals Timer output.

enumerator kFLEXIO_TimerDecSrcOnPinInputShiftPinInput
Decrement counter on Pin input (both edges), Shift clock equals Pin input.

enumerator kFLEXIO_TimerDecSrcOnTriggerInputShiftTriggerInput
Decrement counter on Trigger input (both edges), Shift clock equals Trigger input.

enum _flexio_timer_reset_condition
Define type of timer reset condition.
Values:

enumerator kFLEXIO_TimerResetNever
Timer never reset.

enumerator kFLEXIO_TimerResetOnTimerPinEqualToTimerOutput
Timer reset on Timer Pin equal to Timer Output.

enumerator kFLEXIO_TimerResetOnTimerTriggerEqualToTimerOutput
Timer reset on Timer Trigger equal to Timer Output.

enumerator kFLEXIO_TimerResetOnTimerPinRisingEdge
Timer reset on Timer Pin rising edge.

enumerator kFLEXIO_TimerResetOnTimerTriggerRisingEdge
Timer reset on Trigger rising edge.

enumerator kFLEXIO_TimerResetOnTimerTriggerBothEdge
Timer reset on Trigger rising or falling edge.

enum _flexio_timer_disable_condition
Define type of timer disable condition.
Values:

enumerator kFLEXIO_TimerDisableNever
Timer never disabled.

enumerator kFLEXIO_TimerDisableOnPreTimerDisable
Timer disabled on Timer N-1 disable.

enumerator kFLEXIO_TimerDisableOnTimerCompare
Timer disabled on Timer compare.

enumerator kFLEXIO_TimerDisableOnTimerCompareTriggerLow
Timer disabled on Timer compare and Trigger Low.

enumerator kFLEXIO_TimerDisableOnPinBothEdge
Timer disabled on Pin rising or falling edge.

enumerator kFLEXIO_TimerDisableOnPinBothEdgeTriggerHigh
Timer disabled on Pin rising or falling edge provided Trigger is high.

enumerator kFLEXIO_TimerDisableOnTriggerFallingEdge
Timer disabled on Trigger falling edge.

enum _flexio_timer_enable_condition
Define type of timer enable condition.
Values:

enumerator kFLEXIO_TimerEnabledAlways
Timer always enabled.

enumerator kFLEXIO_TimerEnableOnPrevTimerEnable
Timer enabled on Timer N-1 enable.

enumerator kFLEXIO_TimerEnableOnTriggerHigh
Timer enabled on Trigger high.

enumerator kFLEXIO_TimerEnableOnTriggerHighPinHigh
Timer enabled on Trigger high and Pin high.

enumerator kFLEXIO_TimerEnableOnPinRisingEdge
Timer enabled on Pin rising edge.

enumerator kFLEXIO_TimerEnableOnPinRisingEdgeTriggerHigh
Timer enabled on Pin rising edge and Trigger high.

enumerator kFLEXIO_TimerEnableOnTriggerRisingEdge
Timer enabled on Trigger rising edge.

enumerator kFLEXIO_TimerEnableOnTriggerBothEdge
Timer enabled on Trigger rising or falling edge.

enum _flexio_timer_stop_bit_condition
Define type of timer stop bit generate condition.
Values:

enumerator kFLEXIO_TimerStopBitDisabled
Stop bit disabled.

enumerator kFLEXIO_TimerStopBitEnableOnTimerCompare
Stop bit is enabled on timer compare.

enumerator kFLEXIO_TimerStopBitEnableOnTimerDisable
Stop bit is enabled on timer disable.

enumerator kFLEXIO_TimerStopBitEnableOnTimerCompareDisable
Stop bit is enabled on timer compare and timer disable.

enum _flexio_timer_start_bit_condition
Define type of timer start bit generate condition.
Values:

enumerator kFLEXIO_TimerStartBitDisabled
Start bit disabled.

enumerator kFLEXIO_TimerStartBitEnabled
Start bit enabled.

enum _flexio_timer_output_state
FlexIO as PWM channel output state.
Values:

enumerator kFLEXIO_PwmLow
The output state of PWM channel is low

enumerator kFLEXIO_PwmHigh
The output state of PWM channel is high

enum _flexio_shifter_timer_polarity
Define type of timer polarity for shifter control.
Values:

enumerator kFLEXIO_ShifterTimerPolarityOnPositive
Shift on positive edge of shift clock.

enumerator kFLEXIO_ShifterTimerPolarityOnNegitive
Shift on negative edge of shift clock.

enum _flexio_shifter_mode
Define type of shifter working mode.
Values:

enumerator kFLEXIO_ShifterDisabled
Shifter is disabled.

enumerator kFLEXIO_ShifterModeReceive
Receive mode.

enumerator kFLEXIO_ShifterModeTransmit
Transmit mode.

enumerator kFLEXIO_ShifterModeMatchStore
Match store mode.

enumerator kFLEXIO_ShifterModeMatchContinuous
Match continuous mode.

enumerator kFLEXIO_ShifterModeState
SHIFTBUF contents are used for storing programmable state attributes.

enumerator kFLEXIO_ShifterModeLogic
SHIFTBUF contents are used for implementing programmable logic look up table.

enum _flexio_shifter_input_source
Define type of shifter input source.
Values:

enumerator kFLEXIO_ShifterInputFromPin
Shifter input from pin.

enumerator kFLEXIO_ShifterInputFromNextShifterOutput
Shifter input from Shifter N+1.

enum _flexio_shifter_stop_bit
Define of STOP bit configuration.
Values:

enumerator kFLEXIO_ShifterStopBitDisable
Disable shifter stop bit.

enumerator kFLEXIO_ShifterStopBitLow
Set shifter stop bit to logic low level.

enumerator kFLEXIO_ShifterStopBitHigh
Set shifter stop bit to logic high level.

enum _flexio_shifter_start_bit
Define type of START bit configuration.
Values:

enumerator kFLEXIO_ShifterStartBitDisabledLoadDataOnEnable
Disable shifter start bit, transmitter loads data on enable.

enumerator kFLEXIO_ShifterStartBitDisabledLoadDataOnShift
Disable shifter start bit, transmitter loads data on first shift.

enumerator kFLEXIO_ShifterStartBitLow
Set shifter start bit to logic low level.

enumerator kFLEXIO_ShifterStartBitHigh
Set shifter start bit to logic high level.

enum _flexio_shifter_buffer_type
Define FlexIO shifter buffer type.
Values:

enumerator kFLEXIO_ShifterBuffer
Shifter Buffer N Register.

enumerator kFLEXIO_ShifterBufferBitSwapped
Shifter Buffer N Bit Byte Swapped Register.

enumerator kFLEXIO_ShifterBufferByteSwapped
Shifter Buffer N Byte Swapped Register.

enumerator kFLEXIO_ShifterBufferBitByteSwapped
Shifter Buffer N Bit Swapped Register.

enumerator kFLEXIO_ShifterBufferNibbleByteSwapped
Shifter Buffer N Nibble Byte Swapped Register.

enumerator kFLEXIO_ShifterBufferHalfWordSwapped
Shifter Buffer N Half Word Swapped Register.

enumerator kFLEXIO_ShifterBufferNibbleSwapped
Shifter Buffer N Nibble Swapped Register.

enum _flexio_gpio_direction
FLEXIO gpio direction definition.
Values:

enumerator kFLEXIO_DigitalInput
Set current pin as digital input

enumerator kFLEXIO_DigitalOutput
Set current pin as digital output

enum _flexio_pin_input_config
FLEXIO gpio input config.
Values:

enumerator kFLEXIO_InputInterruptDisabled
Interrupt request is disabled.

enumerator kFLEXIO_InputInterruptEnable
Interrupt request is enable.

enumerator kFLEXIO_FlagRisingEdgeEnable
Input pin flag on rising edge.

enumerator kFLEXIO_FlagFallingEdgeEnable
Input pin flag on falling edge.

typedef enum *_flexio_timer_trigger_polarity* flexio_timer_trigger_polarity_t
Define time of timer trigger polarity.

typedef enum *_flexio_timer_trigger_source* flexio_timer_trigger_source_t
Define type of timer trigger source.

typedef enum *_flexio_pin_config* flexio_pin_config_t
Define type of timer/shifter pin configuration.

typedef enum *_flexio_pin_polarity* flexio_pin_polarity_t
Definition of pin polarity.

typedef enum *_flexio_timer_mode* flexio_timer_mode_t
Define type of timer work mode.

typedef enum *_flexio_timer_output* flexio_timer_output_t
Define type of timer initial output or timer reset condition.

typedef enum *_flexio_timer_decrement_source* flexio_timer_decrement_source_t
Define type of timer decrement.

typedef enum *_flexio_timer_reset_condition* flexio_timer_reset_condition_t
Define type of timer reset condition.

typedef enum *_flexio_timer_disable_condition* flexio_timer_disable_condition_t
Define type of timer disable condition.

typedef enum *_flexio_timer_enable_condition* flexio_timer_enable_condition_t
Define type of timer enable condition.

typedef enum *_flexio_timer_stop_bit_condition* flexio_timer_stop_bit_condition_t
Define type of timer stop bit generate condition.

typedef enum *_flexio_timer_start_bit_condition* flexio_timer_start_bit_condition_t
Define type of timer start bit generate condition.

typedef enum *_flexio_timer_output_state* flexio_timer_output_state_t

FlexIO as PWM channel output state.

typedef enum *_flexio_shifter_timer_polarity* flexio_shifter_timer_polarity_t

Define type of timer polarity for shifter control.

typedef enum *_flexio_shifter_mode* flexio_shifter_mode_t

Define type of shifter working mode.

typedef enum *_flexio_shifter_input_source* flexio_shifter_input_source_t

Define type of shifter input source.

typedef enum *_flexio_shifter_stop_bit* flexio_shifter_stop_bit_t

Define of STOP bit configuration.

typedef enum *_flexio_shifter_start_bit* flexio_shifter_start_bit_t

Define type of START bit configuration.

typedef enum *_flexio_shifter_buffer_type* flexio_shifter_buffer_type_t

Define FlexIO shifter buffer type.

typedef struct *_flexio_config_* flexio_config_t

Define FlexIO user configuration structure.

typedef struct *_flexio_timer_config* flexio_timer_config_t

Define FlexIO timer configuration structure.

typedef struct *_flexio_shifter_config* flexio_shifter_config_t

Define FlexIO shifter configuration structure.

typedef enum *_flexio_gpio_direction* flexio_gpio_direction_t

FLEXIO gpio direction definition.

typedef enum *_flexio_pin_input_config* flexio_pin_input_config_t

FLEXIO gpio input config.

typedef struct *_flexio_gpio_config* flexio_gpio_config_t

The FLEXIO pin configuration structure.

Each pin can only be configured as either an output pin or an input pin at a time. If configured as an input pin, use inputConfig param. If configured as an output pin, use outputLogic.

typedef void (*flexio_isr_t)(void *base, void *handle)

typedef for FlexIO simulated driver interrupt handler.

FLEXIO_Type *const s_flexioBases[]

Pointers to flexio bases for each instance.

const clock_ip_name_t s_flexioClocks[]

Pointers to flexio clocks for each instance.

void FLEXIO_SetPinConfig(FLEXIO_Type *base, uint32_t pin, *flexio_gpio_config_t* *config)

Configure a FLEXIO pin used by the board.

To Config the FLEXIO PIN, define a pin configuration, as either input or output, in the user file. Then, call the *FLEXIO_SetPinConfig()* function.

This is an example to define an input pin or an output pin configuration.

```
Define a digital input pin configuration,
flexio_gpio_config_t config =
{
  kFLEXIO_DigitalInput,
  0U,
  kFLEXIO_FlagRisingEdgeEnable | kFLEXIO_InputInterruptEnable,
}
Define a digital output pin configuration,
flexio_gpio_config_t config =
{
  kFLEXIO_DigitalOutput,
  0U,
  0U
}
```

Parameters

- base – FlexIO peripheral base address
- pin – FLEXIO pin number.
- config – FLEXIO pin configuration pointer.

FLEXIO_TIMER_TRIGGER_SEL_PININPUT(x)

Calculate FlexIO timer trigger.

FLEXIO_TIMER_TRIGGER_SEL_SHIFTnSTAT(x)

FLEXIO_TIMER_TRIGGER_SEL_TIMn(x)

struct _flexio_config_

#include <fsl_flexio.h> Define FlexIO user configuration structure.

Public Members

bool enableFlexio

Enable/disable FlexIO module

bool enableInDoze

Enable/disable FlexIO operation in doze mode

bool enableInDebug

Enable/disable FlexIO operation in debug mode

bool enableFastAccess

Enable/disable fast access to FlexIO registers, fast access requires the FlexIO clock to be at least twice the frequency of the bus clock.

struct _flexio_timer_config

#include <fsl_flexio.h> Define FlexIO timer configuration structure.

Public Members

uint32_t triggerSelect

The internal trigger selection number using MACROs.

flexio_timer_trigger_polarity_t triggerPolarity

Trigger Polarity.

flexio_timer_trigger_source_t triggerSource

Trigger Source, internal (see 'trgsel') or external.

flexio_pin_config_t pinConfig

Timer Pin Configuration.

uint32_t pinSelect

Timer Pin number Select.

flexio_pin_polarity_t pinPolarity

Timer Pin Polarity.

flexio_timer_mode_t timerMode

Timer work Mode.

flexio_timer_output_t timerOutput

Configures the initial state of the Timer Output and whether it is affected by the Timer reset.

flexio_timer_decrement_source_t timerDecrement

Configures the source of the Timer decrement and the source of the Shift clock.

flexio_timer_reset_condition_t timerReset

Configures the condition that causes the timer counter (and optionally the timer output) to be reset.

flexio_timer_disable_condition_t timerDisable

Configures the condition that causes the Timer to be disabled and stop decrementing.

flexio_timer_enable_condition_t timerEnable

Configures the condition that causes the Timer to be enabled and start decrementing.

flexio_timer_stop_bit_condition_t timerStop
: Timer STOP Bit generation.

flexio_timer_start_bit_condition_t timerStart
: Timer STRAT Bit generation.

uint32_t timerCompare
: Value for Timer Compare N Register.

struct __flexio__shifter__config
: *#include <fsl_flexio.h>* Define FlexIO shifter configuration structure.

Public Members

uint32_t timerSelect
: Selects which Timer is used for controlling the logic/shift register and generating the Shift clock.

flexio_shifter_timer_polarity_t timerPolarity
: Timer Polarity.

flexio_pin_config_t pinConfig
: Shifter Pin Configuration.

uint32_t pinSelect
: Shifter Pin number Select.

flexio_pin_polarity_t pinPolarity
: Shifter Pin Polarity.

flexio_shifter_mode_t shifterMode
: Configures the mode of the Shifter.

uint32_t parallelWidth
: Configures the parallel width when using parallel mode.

flexio_shifter_input_source_t inputSource
: Selects the input source for the shifter.

flexio_shifter_stop_bit_t shifterStop
: Shifter STOP bit.

flexio_shifter_start_bit_t shifterStart
: Shifter START bit.

struct __flexio__gpio__config
: *#include <fsl_flexio.h>* The FLEXIO pin configuration structure.

Each pin can only be configured as either an output pin or an input pin at a time. If configured as an input pin, use inputConfig param. If configured as an output pin, use outputLogic.

Public Members

flexio_gpio_direction_t pinDirection

FLEXIO pin direction, input or output

uint8_t outputLogic

Set a default output logic, which has no use in input

uint8_t inputConfig

Set an input config

2.21 FlexIO eDMA I2S Driver

void FLEXIO_I2S_TransferTxCreateHandleEDMA(*FLEXIO_I2S_Type* *base, *flexio_i2s_edma_handle_t* *handle, *flexio_i2s_edma_callback_t* callback, void *userData, *edma_handle_t* *dmaHandle)

Initializes the FlexIO I2S eDMA handle.

This function initializes the FlexIO I2S master DMA handle which can be used for other FlexIO I2S master transactional APIs. Usually, for a specified FlexIO I2S instance, call this API once to get the initialized handle.

Parameters

- base – FlexIO I2S peripheral base address.
- handle – FlexIO I2S eDMA handle pointer.
- callback – FlexIO I2S eDMA callback function called while finished a block.
- userData – User parameter for callback.
- dmaHandle – eDMA handle for FlexIO I2S. This handle is a static value allocated by users.

void FLEXIO_I2S_TransferRxCreateHandleEDMA(*FLEXIO_I2S_Type* *base, *flexio_i2s_edma_handle_t* *handle, *flexio_i2s_edma_callback_t* callback, void *userData, *edma_handle_t* *dmaHandle)

Initializes the FlexIO I2S Rx eDMA handle.

This function initializes the FlexIO I2S slave DMA handle which can be used for other FlexIO I2S master transactional APIs. Usually, for a specified FlexIO I2S instance, call this API once to get the initialized handle.

Parameters

- base – FlexIO I2S peripheral base address.
- handle – FlexIO I2S eDMA handle pointer.
- callback – FlexIO I2S eDMA callback function called while finished a block.
- userData – User parameter for callback.

- dmaHandle – eDMA handle for FlexIO I2S. This handle is a static value allocated by users.

void FLEXIO_I2S_TransferSetFormatEDMA(*FLEXIO_I2S_Type* *base, *flexio_i2s_edma_handle_t* *handle, *flexio_i2s_format_t* *format, uint32_t srcClock_Hz)

Configures the FlexIO I2S Tx audio format.

Audio format can be changed in run-time of FlexIO I2S. This function configures the sample rate and audio data format to be transferred. This function also sets the eDMA parameter according to format.

Parameters

- base – FlexIO I2S peripheral base address.
- handle – FlexIO I2S eDMA handle pointer
- format – Pointer to FlexIO I2S audio data format structure.
- srcClock_Hz – FlexIO I2S clock source frequency in Hz, it should be 0 while in slave mode.

status_t FLEXIO_I2S_TransferSendEDMA(*FLEXIO_I2S_Type* *base, *flexio_i2s_edma_handle_t* *handle, *flexio_i2s_transfer_t* *xfer)

Performs a non-blocking FlexIO I2S transfer using DMA.

Note: This interface returned immediately after transfer initiates. Users should call FLEXIO_I2S_GetTransferStatus to poll the transfer status and check whether the FlexIO I2S transfer is finished.

Parameters

- base – FlexIO I2S peripheral base address.
- handle – FlexIO I2S DMA handle pointer.
- xfer – Pointer to DMA transfer structure.

Return values

- kStatus_Success – Start a FlexIO I2S eDMA send successfully.
- kStatus_InvalidArgument – The input arguments is invalid.
- kStatus_TxBusy – FlexIO I2S is busy sending data.

status_t FLEXIO_I2S_TransferReceiveEDMA(*FLEXIO_I2S_Type* *base, *flexio_i2s_edma_handle_t* *handle, *flexio_i2s_transfer_t* *xfer)

Performs a non-blocking FlexIO I2S receive using eDMA.

Note: This interface returned immediately after transfer initiates. Users should call FLEXIO_I2S_GetReceiveRemainingBytes to poll the transfer status and check whether the FlexIO I2S transfer is finished.

Parameters

- base – FlexIO I2S peripheral base address.
- handle – FlexIO I2S DMA handle pointer.
- xfer – Pointer to DMA transfer structure.

Return values

- kStatus_Success – Start a FlexIO I2S eDMA receive successfully.
- kStatus_InvalidArgument – The input arguments is invalid.
- kStatus_RxBusy – FlexIO I2S is busy receiving data.

void FLEXIO_I2S_TransferAbortSendEDMA(*FLEXIO_I2S_Type* *base, *flexio_i2s_edma_handle_t* *handle)

Aborts a FlexIO I2S transfer using eDMA.

Parameters

- base – FlexIO I2S peripheral base address.
- handle – FlexIO I2S DMA handle pointer.

void FLEXIO_I2S_TransferAbortReceiveEDMA(*FLEXIO_I2S_Type* *base, *flexio_i2s_edma_handle_t* *handle)

Aborts a FlexIO I2S receive using eDMA.

Parameters

- base – FlexIO I2S peripheral base address.
- handle – FlexIO I2S DMA handle pointer.

status_t FLEXIO_I2S_TransferGetSendCountEDMA(*FLEXIO_I2S_Type* *base, *flexio_i2s_edma_handle_t* *handle, size_t *count)

Gets the remaining bytes to be sent.

Parameters

- base – FlexIO I2S peripheral base address.
- handle – FlexIO I2S DMA handle pointer.
- count – Bytes sent.

Return values

- kStatus_Success – Succeed get the transfer count.
- kStatus_NoTransferInProgress – There is not a non-blocking transaction currently in progress.

status_t FLEXIO_I2S_TransferGetReceiveCountEDMA(*FLEXIO_I2S_Type* *base, *flexio_i2s_edma_handle_t* *handle, size_t *count)

Get the remaining bytes to be received.

Parameters

- base – FlexIO I2S peripheral base address.
- handle – FlexIO I2S DMA handle pointer.
- count – Bytes received.

Return values

- kStatus_Success – Succeed get the transfer count.
- kStatus_NoTransferInProgress – There is not a non-blocking transaction currently in progress.

FSL_FLEXIO_I2S_EDMA_DRIVER_VERSION

FlexIO I2S EDMA driver version 2.1.9.

typedef struct *_flexio_i2s_edma_handle* flexio_i2s_edma_handle_t

typedef void (*flexio_i2s_edma_callback_t)(*FLEXIO_I2S_Type* *base, *flexio_i2s_edma_handle_t* *handle, *status_t* status, void *userData)

FlexIO I2S eDMA transfer callback function for finish and error.

struct __flexio_i2s_edma_handle

#include <fsl_flexio_i2s_edma.h> FlexIO I2S DMA transfer handle, users should not touch the content of the handle.

Public Members

edma_handle_t *dmaHandle

DMA handler for FlexIO I2S send

uint8_t bytesPerFrame

Bytes in a frame

uint8_t nbytes

eDMA minor byte transfer count initially configured.

uint32_t state

Internal state for FlexIO I2S eDMA transfer

flexio_i2s_edma_callback_t callback

Callback for users while transfer finish or error occurred

void *userData

User callback parameter

edma_tcd_t tcd[(4U) + 1U]

TCD pool for eDMA transfer.

flexio_i2s_transfer_t queue[(4U)]

Transfer queue storing queued transfer.

size_t transferSize[(4U)]

Data bytes need to transfer

volatile uint8_t queueUser

Index for user to queue transfer.

volatile uint8_t queueDriver

Index for driver to get the transfer data and size

2.22 FlexIO eDMA MCU Interface LCD Driver

status_t FLEXIO_MCULCD_TransferCreateHandleEDMA(*FLEXIO_MCULCD_Type* *base, *flexio_mculcd_edma_handle_t* *handle, *flexio_mculcd_edma_transfer_callback_t* callback, void *userData, *edma_handle_t* *txDmaHandle, *edma_handle_t* *rxDmaHandle)

Initializes the FLEXO MCULCD master eDMA handle.

This function initializes the FLEXO MCULCD master eDMA handle which can be used for other FLEXO MCULCD transactional APIs. For a specified FLEXO MCULCD instance, call this API once to get the initialized handle.

Parameters

- base – Pointer to FLEXIO_MCULCD_Type structure.
- handle – Pointer to flexio_mculcd_edma_handle_t structure to store the transfer state.
- callback – MCULCD transfer complete callback, NULL means no callback.
- userData – callback function parameter.
- txDmaHandle – User requested eDMA handle for FlexIO MCULCD eDMA TX, the DMA request source of this handle should be the first of TX shifters.
- rxDmaHandle – User requested eDMA handle for FlexIO MCULCD eDMA RX, the DMA request source of this handle should be the last of RX shifters.

Return values

kStatus_Success – Successfully create the handle.

status_t FLEXIO_MCULCD_TransferEDMA(*FLEXIO_MCULCD_Type* *base, *flexio_mculcd_edma_handle_t* *handle, *flexio_mculcd_transfer_t* *xfer)

Performs a non-blocking FlexIO MCULCD transfer using eDMA.

This function returns immediately after transfer initiates. To check whether the transfer is completed, user could:

a. Use the transfer completed callback;

b. Polling function FLEXIO_MCULCD_GetTransferCountEDMA

Parameters

- base – pointer to FLEXIO_MCULCD_Type structure.
- handle – pointer to flexio_mculcd_edma_handle_t structure to store the transfer state.
- xfer – Pointer to FlexIO MCULCD transfer structure.

Return values

- kStatus_Success – Successfully start a transfer.
- kStatus_InvalidArgument – Input argument is invalid.
- kStatus_FLEXIO_MCULCD_Busy – FlexIO MCULCD is not idle, it is running another transfer.

void FLEXIO_MCULCD_TransferAbortEDMA(*FLEXIO_MCULCD_Type* *base, *flexio_mculcd_edma_handle_t* *handle)

Aborts a FlexIO MCULCD transfer using eDMA.

Parameters

- base – pointer to FLEXIO_MCULCD_Type structure.
- handle – FlexIO MCULCD eDMA handle pointer.

status_t FLEXIO_MCULCD_TransferGetCountEDMA(*FLEXIO_MCULCD_Type* *base, *flexio_mculcd_edma_handle_t* *handle, size_t *count)

Gets the remaining bytes for FlexIO MCULCD eDMA transfer.

Parameters

- base – pointer to FLEXIO_MCULCD_Type structure.
- handle – FlexIO MCULCD eDMA handle pointer.
- count – Number of count transferred so far by the eDMA transaction.

Return values

- kStatus_Success – Get the transferred count Successfully.
- kStatus_NoTransferInProgress – No transfer in process.

typedef struct *_flexio_mculcd_edma_handle* flexio_mculcd_edma_handle_t

typedef for flexio_mculcd_edma_handle_t in advance.

typedef void (*flexio_mculcd_edma_transfer_callback_t)(*FLEXIO_MCULCD_Type* *base, *flexio_mculcd_edma_handle_t* *handle, *status_t* status, void *userData)

FlexIO MCULCD master callback for transfer complete.

When transfer finished, the callback function is called and returns the status as kStatus_FLEXIO_MCULCD_Idle.

FSL_FLEXIO_MCULCD_EDMA_DRIVER_VERSION

FlexIO MCULCD EDMA driver version.

struct _flexio_mculcd_edma_handle

#include <fsl_flexio_mculcd_edma.h> FlexIO MCULCD eDMA transfer handle, users should not touch the content of the handle.

Public Members

FLEXIO_MCULCD_Type *base

Pointer to the FLEXIO_MCULCD_Type.

uint8_t txShifterNum

Number of shifters used for TX.

uint8_t rxShifterNum

Number of shifters used for RX.

uint32_t minorLoopBytes

eDMA transfer minor loop bytes.

edma_modulo_t txEdmaModulo

Modulo value for the FlexIO shifter buffer access.

edma_modulo_t rxEdmaModulo

Modulo value for the FlexIO shifter buffer access.

uint32_t dataAddrOrSameValue

When sending the same value for many times, this is the value to send. When writing or reading array, this is the address of the data array.

size_t dataCount

Total count to be transferred.

volatile size_t remainingCount

Remaining count still not transfered.

volatile uint32_t state

FlexIO MCULCD driver internal state.

edma_handle_t *txDmaHandle

DMA handle for MCULCD TX

edma_handle_t *rxDmaHandle

DMA handle for MCULCD RX

flexio_mculcd_edma_transfer_callback_t completionCallback

Callback for MCULCD DMA transfer

void *userData

User Data for MCULCD DMA callback

2.23 FlexIO eDMA SPI Driver

status_t FLEXIO_SPI_MasterTransferCreateHandleEDMA(*FLEXIO_SPI_Type* *base, *flexio_spi_master_edma_handle_t* *handle, *flexio_spi_master_edma_transfer_callback_t* callback, void *userData, *edma_handle_t* *txHandle, *edma_handle_t* *rxHandle)

Initializes the FlexIO SPI master eDMA handle.

This function initializes the FlexIO SPI master eDMA handle which can be used for other FlexIO SPI master transactional APIs. For a specified FlexIO SPI instance, call this API once to get the initialized handle.

Parameters

- base – Pointer to FLEXIO_SPI_Type structure.
- handle – Pointer to flexio_spi_master_edma_handle_t structure to store the transfer state.
- callback – SPI callback, NULL means no callback.
- userData – callback function parameter.
- txHandle – User requested eDMA handle for FlexIO SPI RX eDMA transfer.
- rxHandle – User requested eDMA handle for FlexIO SPI TX eDMA transfer.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_OutOfRange – The FlexIO SPI eDMA type/handle table out of range.

status_t FLEXIO_SPI_MasterTransferEDMA(*FLEXIO_SPI_Type* *base, *flexio_spi_master_edma_handle_t* *handle, *flexio_spi_transfer_t* *xfer)

Performs a non-blocking FlexIO SPI transfer using eDMA.

Note: This interface returns immediately after transfer initiates. Call FLEXIO_SPI_MasterGetTransferCountEDMA to poll the transfer status and check whether the FlexIO SPI transfer is finished.

Parameters

- base – Pointer to FLEXIO_SPI_Type structure.
- handle – Pointer to flexio_spi_master_edma_handle_t structure to store the transfer state.
- xfer – Pointer to FlexIO SPI transfer structure.

Return values

- kStatus_Success – Successfully start a transfer.
- kStatus_InvalidArgument – Input argument is invalid.
- kStatus_FLEXIO_SPI_Busy – FlexIO SPI is not idle, is running another transfer.

void FLEXIO_SPI_MasterTransferAbortEDMA(*FLEXIO_SPI_Type* *base, *flexio_spi_master_edma_handle_t* *handle)

Aborts a FlexIO SPI transfer using eDMA.

Parameters

- base – Pointer to FLEXIO_SPI_Type structure.
- handle – FlexIO SPI eDMA handle pointer.

status_t FLEXIO_SPI_MasterTransferGetCountEDMA(*FLEXIO_SPI_Type* *base, *flexio_spi_master_edma_handle_t* *handle, size_t *count)

Gets the number of bytes transferred so far using FlexIO SPI master eDMA.

Parameters

- base – Pointer to FLEXIO_SPI_Type structure.
- handle – FlexIO SPI eDMA handle pointer.
- count – Number of bytes transferred so far by the non-blocking transaction.

static inline void FLEXIO_SPI_SlaveTransferCreateHandleEDMA(*FLEXIO_SPI_Type* *base, *flexio_spi_slave_edma_handle_t* *handle, *flexio_spi_slave_edma_transfer_callback_t* callback, void *userData, *edma_handle_t* *txHandle, *edma_handle_t* *rxHandle)

Initializes the FlexIO SPI slave eDMA handle.

This function initializes the FlexIO SPI slave eDMA handle.

Parameters

- base – Pointer to FLEXIO_SPI_Type structure.
- handle – Pointer to flexio_spi_slave_edma_handle_t structure to store the transfer state.
- callback – SPI callback, NULL means no callback.
- userData – callback function parameter.
- txHandle – User requested eDMA handle for FlexIO SPI TX eDMA transfer.
- rxHandle – User requested eDMA handle for FlexIO SPI RX eDMA transfer.

status_t FLEXIO_SPI_SlaveTransferEDMA(*FLEXIO_SPI_Type* *base, *flexio_spi_slave_edma_handle_t* *handle, *flexio_spi_transfer_t* *xfer)

Performs a non-blocking FlexIO SPI transfer using eDMA.

Note: This interface returns immediately after transfer initiates. Call FLEXIO_SPI_SlaveGetTransferCountEDMA to poll the transfer status and check whether the FlexIO SPI transfer is finished.

Parameters

- base – Pointer to FLEXIO_SPI_Type structure.
- handle – Pointer to flexio_spi_slave_edma_handle_t structure to store the transfer state.
- xfer – Pointer to FlexIO SPI transfer structure.

Return values

- kStatus_Success – Successfully start a transfer.
- kStatus_InvalidArgument – Input argument is invalid.
- kStatus_FLEXIO_SPI_Busy – FlexIO SPI is not idle, is running another transfer.

static inline void FLEXIO_SPI_SlaveTransferAbortEDMA(*FLEXIO_SPI_Type* *base, *flexio_spi_slave_edma_handle_t* *handle)

Aborts a FlexIO SPI transfer using eDMA.

Parameters

- base – Pointer to FLEXIO_SPI_Type structure.
- handle – Pointer to flexio_spi_slave_edma_handle_t structure to store the transfer state.

static inline *status_t* FLEXIO_SPI_SlaveTransferGetCountEDMA(*FLEXIO_SPI_Type* *base, *flexio_spi_slave_edma_handle_t* *handle, size_t *count)

Gets the number of bytes transferred so far using FlexIO SPI slave eDMA.

Parameters

- base – Pointer to FLEXIO_SPI_Type structure.
- handle – FlexIO SPI eDMA handle pointer.
- count – Number of bytes transferred so far by the non-blocking transaction.

FSL_FLEXIO_SPI_EDMA_DRIVER_VERSION

FlexIO SPI EDMA driver version.

typedef struct *_flexio_spi_master_edma_handle* flexio_spi_master_edma_handle_t

typedef for flexio_spi_master_edma_handle_t in advance.

typedef *flexio_spi_master_edma_handle_t* flexio_spi_slave_edma_handle_t

Slave handle is the same with master handle.

typedef void (*flexio_spi_master_edma_transfer_callback_t)(*FLEXIO_SPI_Type* *base, *flexio_spi_master_edma_handle_t* *handle, *status_t* status, void *userData)

FlexIO SPI master callback for finished transmit.

typedef void (*flexio_spi_slave_edma_transfer_callback_t)(*FLEXIO_SPI_Type* *base, *flexio_spi_slave_edma_handle_t* *handle, *status_t* status, void *userData)

FlexIO SPI slave callback for finished transmit.

struct _flexio_spi_master_edma_handle

#include <fsl_flexio_spi_edma.h> FlexIO SPI eDMA transfer handle, users should not touch the content of the handle.

Public Members

size_t transferSize

Total bytes to be transferred.

uint8_t nbytes

eDMA minor byte transfer count initially configured.

bool txInProgress

Send transfer in progress

bool rxInProgress

Receive transfer in progress

edma_handle_t *txHandle

DMA handler for SPI send

edma_handle_t *rxHandle
DMA handler for SPI receive

flexio_spi_master_edma_transfer_callback_t callback
Callback for SPI DMA transfer

void *userData
User Data for SPI DMA callback

2.24 FlexIO eDMA UART Driver

status_t FLEXIO_UART_TransferCreateHandleEDMA(*FLEXIO_UART_Type* *base, *flexio_uart_edma_handle_t* *handle, *flexio_uart_edma_transfer_callback_t* callback, void *userData, *edma_handle_t* *txEdmaHandle, *edma_handle_t* *rxEdmaHandle)

Initializes the UART handle which is used in transactional functions.

Parameters

- base – Pointer to FLEXIO_UART_Type.
- handle – Pointer to flexio_uart_edma_handle_t structure.
- callback – The callback function.
- userData – The parameter of the callback function.
- rxEdmaHandle – User requested DMA handle for RX DMA transfer.
- txEdmaHandle – User requested DMA handle for TX DMA transfer.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_OutOfRange – The FlexIO SPI eDMA type/handle table out of range.

status_t FLEXIO_UART_TransferSendEDMA(*FLEXIO_UART_Type* *base, *flexio_uart_edma_handle_t* *handle, *flexio_uart_transfer_t* *xfer)

Sends data using eDMA.

This function sends data using eDMA. This is a non-blocking function, which returns right away. When all data is sent out, the send callback function is called.

Parameters

- base – Pointer to FLEXIO_UART_Type
- handle – UART handle pointer.
- xfer – UART eDMA transfer structure, see *flexio_uart_transfer_t*.

Return values

- kStatus_Success – if succeed, others failed.
- kStatus_FLEXIO_UART_TxBusy – Previous transfer on going.

status_t FLEXIO_UART_TransferReceiveEDMA(*FLEXIO_UART_Type* *base, *flexio_uart_edma_handle_t* *handle, *flexio_uart_transfer_t* *xfer)

Receives data using eDMA.

This function receives data using eDMA. This is a non-blocking function, which returns right away. When all data is received, the receive callback function is called.

Parameters

- base – Pointer to FLEXIO_UART_Type
- handle – Pointer to flexio_uart_edma_handle_t structure
- xfer – UART eDMA transfer structure, see *flexio_uart_transfer_t*.

Return values

- kStatus_Success – if succeed, others failed.
- kStatus_UART_RxBusy – Previous transfer on going.

void FLEXIO_UART_TransferAbortSendEDMA(*FLEXIO_UART_Type* *base, *flexio_uart_edma_handle_t* *handle)

Aborts the sent data which using eDMA.

This function aborts sent data which using eDMA.

Parameters

- base – Pointer to FLEXIO_UART_Type
- handle – Pointer to flexio_uart_edma_handle_t structure

void FLEXIO_UART_TransferAbortReceiveEDMA(*FLEXIO_UART_Type* *base, *flexio_uart_edma_handle_t* *handle)

Aborts the receive data which using eDMA.

This function aborts the receive data which using eDMA.

Parameters

- base – Pointer to FLEXIO_UART_Type
- handle – Pointer to flexio_uart_edma_handle_t structure

status_t FLEXIO_UART_TransferGetSendCountEDMA(*FLEXIO_UART_Type* *base, *flexio_uart_edma_handle_t* *handle, size_t *count)

Gets the number of bytes sent out.

This function gets the number of bytes sent out.

Parameters

- base – Pointer to FLEXIO_UART_Type
- handle – Pointer to flexio_uart_edma_handle_t structure
- count – Number of bytes sent so far by the non-blocking transaction.

Return values

- kStatus_NoTransferInProgress – transfer has finished or no transfer in progress.
- kStatus_Success – Successfully return the count.

status_t FLEXIO_UART_TransferGetReceiveCountEDMA(*FLEXIO_UART_Type* *base, *flexio_uart_edma_handle_t* *handle, size_t *count)

Gets the number of bytes received.

This function gets the number of bytes received.

Parameters

- base – Pointer to FLEXIO_UART_Type
- handle – Pointer to flexio_uart_edma_handle_t structure
- count – Number of bytes received so far by the non-blocking transaction.

Return values

- kStatus_NoTransferInProgress – transfer has finished or no transfer in progress.
- kStatus_Success – Successfully return the count.

FSL_FLEXIO_UART_EDMA_DRIVER_VERSION

FlexIO UART EDMA driver version.

typedef struct *_flexio_uart_edma_handle* flexio_uart_edma_handle_t

typedef void (*flexio_uart_edma_transfer_callback_t)(*FLEXIO_UART_Type* *base, *flexio_uart_edma_handle_t* *handle, *status_t* status, void *userData)

UART transfer callback function.

struct _flexio_uart_edma_handle

#include <fsl_flexio_uart_edma.h> UART eDMA handle.

Public Members

flexio_uart_edma_transfer_callback_t callback

Callback function.

void *userData

UART callback function parameter.

size_t txDataSizeAll

Total bytes to be sent.

size_t rxDataSizeAll

Total bytes to be received.

edma_handle_t *txEdmaHandle

The eDMA TX channel used.

edma_handle_t *rxEdmaHandle

The eDMA RX channel used.

uint8_t nbytes
: eDMA minor byte transfer count initially configured.

volatile uint8_t txState
: TX transfer state.

volatile uint8_t rxState
: RX transfer state

2.25 FlexIO I2C Master Driver

status_t FLEXIO_I2C_CheckForBusyBus(*FLEXIO_I2C_Type* *base)

Make sure the bus isn't already pulled down.

Check the FLEXIO pin status to see whether either of SDA and SCL pin is pulled down.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure..

Return values

- kStatus_Success –
- kStatus_FLEXIO_I2C_Busy –

status_t FLEXIO_I2C_MasterInit(*FLEXIO_I2C_Type* *base, *flexio_i2c_master_config_t* *masterConfig, uint32_t srcClock_Hz)

Ungates the FlexIO clock, resets the FlexIO module, and configures the FlexIO I2C hardware configuration.

Example

```
FLEXIO_I2C_Type base = {
.flexioBase = FLEXIO,
.SDAPinIndex = 0,
.SCLPinIndex = 1,
.shifterIndex = {0,1},
.timerIndex = {0,1}
};
flexio_i2c_master_config_t config = {
.enableInDoze = false,
.enableInDebug = true,
.enableFastAccess = false,
.baudRate_Bps = 100000
};
FLEXIO_I2C_MasterInit(base, &config, srcClock_Hz);
```

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- masterConfig – Pointer to flexio_i2c_master_config_t structure.
- srcClock_Hz – FlexIO source clock in Hz.

Return values

- kStatus_Success – Initialization successful
- kStatus_InvalidArgument – The source clock exceed upper range limitation

void FLEXIO_I2C_MasterDeinit(*FLEXIO_I2C_Type* *base)

De-initializes the FlexIO I2C master peripheral. Calling this API Resets the FlexIO I2C master shifer and timer config, module can't work unless the FLEXIO_I2C_MasterInit is called.

Parameters

- base – pointer to FLEXIO_I2C_Type structure.

void FLEXIO_I2C_MasterGetDefaultConfig(*flexio_i2c_master_config_t* *masterConfig)

Gets the default configuration to configure the FlexIO module. The configuration can be used directly for calling the *FLEXIO_I2C_MasterInit()*.

Example:

```
flexio_i2c_master_config_t config;
FLEXIO_I2C_MasterGetDefaultConfig(&config);
```

Parameters

- masterConfig – Pointer to flexio_i2c_master_config_t structure.

static inline void FLEXIO_I2C_MasterEnable(*FLEXIO_I2C_Type* *base, bool enable)

Enables/disables the FlexIO module operation.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- enable – Pass true to enable module, false does not have any effect.

uint32_t FLEXIO_I2C_MasterGetStatusFlags(*FLEXIO_I2C_Type* *base)

Gets the FlexIO I2C master status flags.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure

Returns

Status flag, use status flag to AND *_flexio_i2c_master_status_flags* can get the related status.

void FLEXIO_I2C_MasterClearStatusFlags(*FLEXIO_I2C_Type* *base, uint32_t mask)

Clears the FlexIO I2C master status flags.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- mask – Status flag. The parameter can be any combination of the following values:
  - kFLEXIO_I2C_RxFullFlag
  - kFLEXIO_I2C_ReceiveNakFlag

void FLEXIO_I2C_MasterEnableInterrupts(*FLEXIO_I2C_Type* *base, uint32_t mask)

Enables the FlexIO i2c master interrupt requests.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- mask – Interrupt source. Currently only one interrupt request source:
  - kFLEXIO_I2C_TransferCompleteInterruptEnable

void FLEXIO_I2C_MasterDisableInterrupts(*FLEXIO_I2C_Type* *base, uint32_t mask)

Disables the FlexIO I2C master interrupt requests.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- mask – Interrupt source.

void FLEXIO_I2C_MasterSetBaudRate(*FLEXIO_I2C_Type* *base, uint32_t baudRate_Bps, uint32_t srcClock_Hz)

Sets the FlexIO I2C master transfer baudrate.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure
- baudRate_Bps – the baud rate value in HZ
- srcClock_Hz – source clock in HZ

void FLEXIO_I2C_MasterStart(*FLEXIO_I2C_Type* *base, uint8_t address, *flexio_i2c_direction_t* direction)

Sends START + 7-bit address to the bus.

Note: This API should be called when the transfer configuration is ready to send a START signal and 7-bit address to the bus. This is a non-blocking API, which returns directly after the address is put into the data register but the address transfer is not finished on the bus. Ensure that the kFLEXIO_I2C_RxFullFlag status is asserted before calling this API.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- address – 7-bit address.
- direction – transfer direction. This parameter is one of the values in flexio_i2c_direction_t:
  - kFLEXIO_I2C_Write: Transmit
  - kFLEXIO_I2C_Read: Receive

void FLEXIO_I2C_MasterStop(*FLEXIO_I2C_Type* *base)

Sends the stop signal on the bus.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.

void FLEXIO_I2C_MasterRepeatedStart(*FLEXIO_I2C_Type* *base)

Sends the repeated start signal on the bus.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.

void FLEXIO_I2C_MasterAbortStop(*FLEXIO_I2C_Type* *base)

Sends the stop signal when transfer is still on-going.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.

void FLEXIO_I2C_MasterEnableAck(*FLEXIO_I2C_Type* *base, bool enable)

Configures the sent ACK/NAK for the following byte.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- enable – True to configure send ACK, false configure to send NAK.

status_t FLEXIO_I2C_MasterSetTransferCount(*FLEXIO_I2C_Type* *base, uint16_t count)

Sets the number of bytes to be transferred from a start signal to a stop signal.

Note: Call this API before a transfer begins because the timer generates a number of clocks according to the number of bytes that need to be transferred.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- count – Number of bytes need to be transferred from a start signal to a re-start/stop signal

Return values

- kStatus_Success – Successfully configured the count.
- kStatus_InvalidArgument – Input argument is invalid.

static inline void FLEXIO_I2C_MasterWriteByte(*FLEXIO_I2C_Type* *base, uint32_t data)

Writes one byte of data to the I2C bus.

Note: This is a non-blocking API, which returns directly after the data is put into the data register but the data transfer is not finished on the bus. Ensure that the TxEmptyFlag is asserted before calling this API.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- data – a byte of data.

static inline uint8_t FLEXIO_I2C_MasterReadByte(*FLEXIO_I2C_Type* *base)

Reads one byte of data from the I2C bus.

Note: This is a non-blocking API, which returns directly after the data is read from the data register. Ensure that the data is ready in the register.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.

Returns

data byte read.

status_t FLEXIO_I2C_MasterWriteBlocking(*FLEXIO_I2C_Type* *base, const uint8_t *txBuff, uint8_t txSize)

Sends a buffer of data in bytes.

Note: This function blocks via polling until all bytes have been sent.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- txBuff – The data bytes to send.
- txSize – The number of data bytes to send.

Return values

- kStatus_Success – Successfully write data.
- kStatus_FLEXIO_I2C_Nak – Receive NAK during writing data.
- kStatus_FLEXIO_I2C_Timeout – Timeout polling status flags.

status_t FLEXIO_I2C_MasterReadBlocking(*FLEXIO_I2C_Type* *base, uint8_t *rxBuff, uint8_t rxSize)

Receives a buffer of bytes.

Note: This function blocks via polling until all bytes have been received.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- rxBuff – The buffer to store the received bytes.
- rxSize – The number of data bytes to be received.

Return values

- kStatus_Success – Successfully read data.
- kStatus_FLEXIO_I2C_Timeout – Timeout polling status flags.

status_t FLEXIO_I2C_MasterTransferBlocking(*FLEXIO_I2C_Type* *base, *flexio_i2c_master_transfer_t* *xfer)

Performs a master polling transfer on the I2C bus.

Note: The API does not return until the transfer succeeds or fails due to receiving NAK.

Parameters

- base – pointer to FLEXIO_I2C_Type structure.
- xfer – pointer to flexio_i2c_master_transfer_t structure.

Returns

status of status_t.

status_t FLEXIO_I2C_MasterTransferCreateHandle(*FLEXIO_I2C_Type* *base, *flexio_i2c_master_handle_t* *handle, *flexio_i2c_master_transfer_callback_t* callback, void *userData)

Initializes the I2C handle which is used in transactional functions.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- handle – Pointer to flexio_i2c_master_handle_t structure to store the transfer state.
- callback – Pointer to user callback function.
- userData – User param passed to the callback function.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_OutOfRange – The FlexIO type/handle/isr table out of range.

status_t FLEXIO_I2C_MasterTransferNonBlocking(*FLEXIO_I2C_Type* *base, *flexio_i2c_master_handle_t* *handle, *flexio_i2c_master_transfer_t* *xfer)

Performs a master interrupt non-blocking transfer on the I2C bus.

Note: The API returns immediately after the transfer initiates. Call FLEXIO_I2C_MasterTransferGetCount to poll the transfer status to check whether the transfer is finished. If the return status is not kStatus_FLEXIO_I2C_Busy, the transfer is finished.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure
- handle – Pointer to flexio_i2c_master_handle_t structure which stores the transfer state
- xfer – pointer to flexio_i2c_master_transfer_t structure

Return values

- kStatus_Success – Successfully start a transfer.
- kStatus_FLEXIO_I2C_Busy – FlexIO I2C is not idle, is running another transfer.

status_t FLEXIO_I2C_MasterTransferGetCount(*FLEXIO_I2C_Type* *base, *flexio_i2c_master_handle_t* *handle, size_t *count)

Gets the master transfer status during a interrupt non-blocking transfer.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- handle – Pointer to flexio_i2c_master_handle_t structure which stores the transfer state.
- count – Number of bytes transferred so far by the non-blocking transaction.

Return values

- kStatus_InvalidArgument – count is Invalid.
- kStatus_NoTransferInProgress – There is not a non-blocking transaction currently in progress.
- kStatus_Success – Successfully return the count.

void FLEXIO_I2C_MasterTransferAbort(*FLEXIO_I2C_Type* *base, *flexio_i2c_master_handle_t* *handle)

Aborts an interrupt non-blocking transfer early.

Note: This API can be called at any time when an interrupt non-blocking transfer initiates to abort the transfer early.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure
- handle – Pointer to flexio_i2c_master_handle_t structure which stores the transfer state

void FLEXIO_I2C_MasterTransferHandleIRQ(void *i2cType, void *i2cHandle)

Master interrupt handler.

Parameters

- i2cType – Pointer to FLEXIO_I2C_Type structure
- i2cHandle – Pointer to flexio_i2c_master_transfer_t structure

FSL_FLEXIO_I2C_MASTER_DRIVER_VERSION

FlexIO I2C transfer status.

Values:

enumerator kStatus_FLEXIO_I2C_Busy

I2C is busy doing transfer.

enumerator kStatus_FLEXIO_I2C_Idle

I2C is busy doing transfer.

enumerator kStatus_FLEXIO_I2C_Nak

NAK received during transfer.

enumerator kStatus_FLEXIO_I2C_Timeout

Timeout polling status flags.

enum _flexio_i2c_master_interrupt

Define FlexIO I2C master interrupt mask.

Values:

enumerator kFLEXIO_I2C_TxEmptyInterruptEnable

Tx buffer empty interrupt enable.

enumerator kFLEXIO_I2C_RxFullInterruptEnable

Rx buffer full interrupt enable.

enum _flexio_i2c_master_status_flags

Define FlexIO I2C master status mask.

Values:

enumerator kFLEXIO_I2C_TxEmptyFlag

Tx shifter empty flag.

enumerator kFLEXIO_I2C_RxFullFlag

Rx shifter full/Transfer complete flag.

enumerator kFLEXIO_I2C_ReceiveNakFlag

Receive NAK flag.

enum _flexio_i2c_direction

Direction of master transfer.

Values:

enumerator kFLEXIO_I2C_Write

Master send to slave.

enumerator kFLEXIO_I2C_Read

Master receive from slave.

typedef enum *_flexio_i2c_direction* flexio_i2c_direction_t

Direction of master transfer.

typedef struct *_flexio_i2c_type* FLEXIO_I2C_Type

Define FlexIO I2C master access structure typedef.

typedef struct *_flexio_i2c_master_config* flexio_i2c_master_config_t

Define FlexIO I2C master user configuration structure.

typedef struct *_flexio_i2c_master_transfer* flexio_i2c_master_transfer_t

Define FlexIO I2C master transfer structure.

typedef struct *_flexio_i2c_master_handle* flexio_i2c_master_handle_t

FlexIO I2C master handle typedef.

typedef void (*flexio_i2c_master_transfer_callback_t)(*FLEXIO_I2C_Type* *base, *flexio_i2c_master_handle_t* *handle, *status_t* status, void *userData)

FlexIO I2C master transfer callback typedef.

I2C_RETRY_TIMES

Retry times for waiting flag.

struct _flexio_i2c_type

#include <fsl_flexio_i2c_master.h> Define FlexIO I2C master access structure typedef.

Public Members

FLEXIO_Type *flexioBase
: FlexIO base pointer.

uint8_t SDAPinIndex
: Pin select for I2C SDA.

uint8_t SCLPinIndex
: Pin select for I2C SCL.

uint8_t shifterIndex[2]
: Shifter index used in FlexIO I2C.

uint8_t timerIndex[3]
: Timer index used in FlexIO I2C.

uint32_t baudrate
: Master transfer baudrate, used to calculate delay time.

struct __flexio_i2c_master_config
: *#include <fsl_flexio_i2c_master.h>* Define FlexIO I2C master user configuration structure.

Public Members

bool enableMaster
: Enables the FlexIO I2C peripheral at initialization time.

bool enableInDoze
: Enable/disable FlexIO operation in doze mode.

bool enableInDebug
: Enable/disable FlexIO operation in debug mode.

bool enableFastAccess
: Enable/disable fast access to FlexIO registers, fast access requires the FlexIO clock to be at least twice the frequency of the bus clock.

uint32_t baudRate_Bps
: Baud rate in Bps.

struct __flexio_i2c_master_transfer
: *#include <fsl_flexio_i2c_master.h>* Define FlexIO I2C master transfer structure.

Public Members

uint32_t flags
: Transfer flag which controls the transfer, reserved for FlexIO I2C.

uint8_t slaveAddress
: 7-bit slave address.

flexio_i2c_direction_t direction
: Transfer direction, read or write.

uint32_t subaddress
: Sub address. Transferred MSB first.

uint8_t subaddressSize
: Size of sub address.

uint8_t volatile *data
: Transfer buffer.

volatile size_t dataSize
: Transfer size.

struct _flexio_i2c_master_handle
: *#include <fsl_flexio_i2c_master.h>* Define FlexIO I2C master handle structure.

Public Members

flexio_i2c_master_transfer_t transfer
: FlexIO I2C master transfer copy.

size_t transferSize
: Total bytes to be transferred.

uint8_t state
: Transfer state maintained during transfer.

flexio_i2c_master_transfer_callback_t completionCallback
: Callback function called at transfer event. Callback function called at transfer event.

void *userData
: Callback parameter passed to callback function.

bool needRestart
: Whether master needs to send re-start signal.

2.26 FlexIO I2S Driver

void FLEXIO_I2S_Init(*FLEXIO_I2S_Type* *base, const *flexio_i2s_config_t* *config)

Initializes the FlexIO I2S.

This API configures FlexIO pins and shifter to I2S and configures the FlexIO I2S with a configuration structure. The configuration structure can be filled by the user, or be set with default values by *FLEXIO_I2S_GetDefaultConfig()*.

Note: This API should be called at the beginning of the application to use the FlexIO I2S driver. Otherwise, any access to the FlexIO I2S module can cause hard fault because the clock is not enabled.

Parameters

- base – FlexIO I2S base pointer
- config – FlexIO I2S configure structure.

void FLEXIO_I2S_GetDefaultConfig(*flexio_i2s_config_t* *config)

Sets the FlexIO I2S configuration structure to default values.

The purpose of this API is to get the configuration structure initialized for use in *FLEXIO_I2S_Init()*. Users may use the initialized structure unchanged in *FLEXIO_I2S_Init()* or modify some fields of the structure before calling *FLEXIO_I2S_Init()*.

Parameters

- config – pointer to master configuration structure

void FLEXIO_I2S_Deinit(*FLEXIO_I2S_Type* *base)

De-initializes the FlexIO I2S.

Calling this API resets the FlexIO I2S shifter and timer config. After calling this API, call the FLEXO_I2S_Init to use the FlexIO I2S module.

Parameters

- base – FlexIO I2S base pointer

static inline void FLEXIO_I2S_Enable(*FLEXIO_I2S_Type* *base, bool enable)

Enables/disables the FlexIO I2S module operation.

Parameters

- base – Pointer to FLEXIO_I2S_Type
- enable – True to enable, false dose not have any effect.

uint32_t FLEXIO_I2S_GetStatusFlags(*FLEXIO_I2S_Type* *base)

Gets the FlexIO I2S status flags.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure

Returns

Status flag, which are ORed by the enumerators in the _flexio_i2s_status_flags.

void FLEXIO_I2S_EnableInterrupts(*FLEXIO_I2S_Type* *base, uint32_t mask)

Enables the FlexIO I2S interrupt.

This function enables the FlexIO UART interrupt.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure
- mask – interrupt source

void FLEXIO_I2S_DisableInterrupts(*FLEXIO_I2S_Type* *base, uint32_t mask)

Disables the FlexIO I2S interrupt.

This function enables the FlexIO UART interrupt.

Parameters

- base – pointer to FLEXIO_I2S_Type structure
- mask – interrupt source

static inline void FLEXIO_I2S_TxEnableDMA(*FLEXIO_I2S_Type* *base, bool enable)

Enables/disables the FlexIO I2S Tx DMA requests.

Parameters

- base – FlexIO I2S base pointer
- enable – True means enable DMA, false means disable DMA.

static inline void FLEXIO_I2S_RxEnableDMA(*FLEXIO_I2S_Type* *base, bool enable)

Enables/disables the FlexIO I2S Rx DMA requests.

Parameters

- base – FlexIO I2S base pointer
- enable – True means enable DMA, false means disable DMA.

static inline uint32_t FLEXIO_I2S_TxGetDataRegisterAddress(*FLEXIO_I2S_Type* *base)

Gets the FlexIO I2S send data register address.

This function returns the I2S data register address, mainly used by DMA/eDMA.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure

Returns

FlexIO i2s send data register address.

static inline uint32_t FLEXIO_I2S_RxGetDataRegisterAddress(*FLEXIO_I2S_Type* *base)

Gets the FlexIO I2S receive data register address.

This function returns the I2S data register address, mainly used by DMA/eDMA.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure

Returns

FlexIO i2s receive data register address.

void FLEXIO_I2S_MasterSetFormat(*FLEXIO_I2S_Type* *base, *flexio_i2s_format_t* *format, uint32_t srcClock_Hz)

Configures the FlexIO I2S audio format in master mode.

Audio format can be changed in run-time of FlexIO I2S. This function configures the sample rate and audio data format to be transferred.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure
- format – Pointer to FlexIO I2S audio data format structure.
- srcClock_Hz – I2S master clock source frequency in Hz.

void FLEXIO_I2S_SlaveSetFormat(*FLEXIO_I2S_Type* *base, *flexio_i2s_format_t* *format)

Configures the FlexIO I2S audio format in slave mode.

Audio format can be changed in run-time of FlexIO I2S. This function configures the sample rate and audio data format to be transferred.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure
- format – Pointer to FlexIO I2S audio data format structure.

status_t FLEXIO_I2S_WriteBlocking(*FLEXIO_I2S_Type* *base, uint8_t bitWidth, uint8_t *txData, size_t size)

Sends data using a blocking method.

Note: This function blocks via polling until data is ready to be sent.

Parameters

- base – FlexIO I2S base pointer.
- bitWidth – How many bits in a audio word, usually 8/16/24/32 bits.
- txData – Pointer to the data to be written.
- size – Bytes to be written.

Return values

- kStatus_Success – Successfully write data.
- kStatus_FLEXIO_I2C_Timeout – Timeout polling status flags.

static inline void FLEXIO_I2S_WriteData(*FLEXIO_I2S_Type* *base, uint8_t bitWidth, uint32_t data)

Writes data into a data register.

Parameters

- base – FlexIO I2S base pointer.
- bitWidth – How many bits in a audio word, usually 8/16/24/32 bits.
- data – Data to be written.

status_t FLEXIO_I2S_ReadBlocking(*FLEXIO_I2S_Type* *base, uint8_t bitWidth, uint8_t *rxData, size_t size)

Receives a piece of data using a blocking method.

Note: This function blocks via polling until data is ready to be sent.

Parameters

- base – FlexIO I2S base pointer
- bitWidth – How many bits in a audio word, usually 8/16/24/32 bits.
- rxData – Pointer to the data to be read.
- size – Bytes to be read.

Return values

- kStatus_Success – Successfully read data.

- kStatus_FLEXIO_I2C_Timeout – Timeout polling status flags.

static inline uint32_t FLEXIO_I2S_ReadData(*FLEXIO_I2S_Type* *base)

Reads a data from the data register.

Parameters

- base – FlexIO I2S base pointer

Returns

Data read from data register.

void FLEXIO_I2S_TransferTxCreateHandle(*FLEXIO_I2S_Type* *base, *flexio_i2s_handle_t* *handle, *flexio_i2s_callback_t* callback, void *userData)

Initializes the FlexIO I2S handle.

This function initializes the FlexIO I2S handle which can be used for other FlexIO I2S transactional APIs. Call this API once to get the initialized handle.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure
- handle – Pointer to flexio_i2s_handle_t structure to store the transfer state.
- callback – FlexIO I2S callback function, which is called while finished a block.
- userData – User parameter for the FlexIO I2S callback.

void FLEXIO_I2S_TransferSetFormat(*FLEXIO_I2S_Type* *base, *flexio_i2s_handle_t* *handle, *flexio_i2s_format_t* *format, uint32_t srcClock_Hz)

Configures the FlexIO I2S audio format.

Audio format can be changed at run-time of FlexIO I2S. This function configures the sample rate and audio data format to be transferred.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure.
- handle – FlexIO I2S handle pointer.
- format – Pointer to audio data format structure.
- srcClock_Hz – FlexIO I2S bit clock source frequency in Hz. This parameter should be 0 while in slave mode.

void FLEXIO_I2S_TransferRxCreateHandle(*FLEXIO_I2S_Type* *base, *flexio_i2s_handle_t* *handle, *flexio_i2s_callback_t* callback, void *userData)

Initializes the FlexIO I2S receive handle.

This function initializes the FlexIO I2S handle which can be used for other FlexIO I2S transactional APIs. Call this API once to get the initialized handle.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure.
- handle – Pointer to flexio_i2s_handle_t structure to store the transfer state.
- callback – FlexIO I2S callback function, which is called while finished a block.
- userData – User parameter for the FlexIO I2S callback.

status_t FLEXIO_I2S_TransferSendNonBlocking(*FLEXIO_I2S_Type* *base, *flexio_i2s_handle_t* *handle, *flexio_i2s_transfer_t* *xfer)

Performs an interrupt non-blocking send transfer on FlexIO I2S.

Note: The API returns immediately after transfer initiates. Call FLEXIO_I2S_GetRemainingBytes to poll the transfer status and check whether the transfer is finished. If the return status is 0, the transfer is finished.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure.
- handle – Pointer to flexio_i2s_handle_t structure which stores the transfer state
- xfer – Pointer to flexio_i2s_transfer_t structure

Return values

- kStatus_Success – Successfully start the data transmission.
- kStatus_FLEXIO_I2S_TxBusy – Previous transmission still not finished, data not all written to TX register yet.
- kStatus_InvalidArgument – The input parameter is invalid.

status_t FLEXIO_I2S_TransferReceiveNonBlocking(*FLEXIO_I2S_Type* *base, *flexio_i2s_handle_t* *handle, *flexio_i2s_transfer_t* *xfer)

Performs an interrupt non-blocking receive transfer on FlexIO I2S.

Note: The API returns immediately after transfer initiates. Call FLEXIO_I2S_GetRemainingBytes to poll the transfer status to check whether the transfer is finished. If the return status is 0, the transfer is finished.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure.
- handle – Pointer to flexio_i2s_handle_t structure which stores the transfer state
- xfer – Pointer to flexio_i2s_transfer_t structure

Return values

- kStatus_Success – Successfully start the data receive.
- kStatus_FLEXIO_I2S_RxBusy – Previous receive still not finished.
- kStatus_InvalidArgument – The input parameter is invalid.

void FLEXIO_I2S_TransferAbortSend(*FLEXIO_I2S_Type* *base, *flexio_i2s_handle_t* *handle)

Aborts the current send.

Note: This API can be called at any time when interrupt non-blocking transfer initiates to abort the transfer in a early time.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure.

- handle – Pointer to flexio_i2s_handle_t structure which stores the transfer state

void FLEXIO_I2S_TransferAbortReceive(*FLEXIO_I2S_Type* *base, *flexio_i2s_handle_t* *handle)

Aborts the current receive.

Note: This API can be called at any time when interrupt non-blocking transfer initiates to abort the transfer in a early time.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure.
- handle – Pointer to flexio_i2s_handle_t structure which stores the transfer state

status_t FLEXIO_I2S_TransferGetSendCount(*FLEXIO_I2S_Type* *base, *flexio_i2s_handle_t* *handle, size_t *count)

Gets the remaining bytes to be sent.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure.
- handle – Pointer to flexio_i2s_handle_t structure which stores the transfer state
- count – Bytes sent.

Return values

- kStatus_Success – Succeed get the transfer count.
- kStatus_NoTransferInProgress – There is not a non-blocking transaction currently in progress.

status_t FLEXIO_I2S_TransferGetReceiveCount(*FLEXIO_I2S_Type* *base, *flexio_i2s_handle_t* *handle, size_t *count)

Gets the remaining bytes to be received.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure.
- handle – Pointer to flexio_i2s_handle_t structure which stores the transfer state
- count – Bytes recieved.

Return values

- kStatus_Success – Succeed get the transfer count.
- kStatus_NoTransferInProgress – There is not a non-blocking transaction currently in progress.

Returns

count Bytes received.

void FLEXIO_I2S_TransferTxHandleIRQ(void *i2sBase, void *i2sHandle)

Tx interrupt handler.

Parameters

- i2sBase – Pointer to FLEXIO_I2S_Type structure.

- i2sHandle – Pointer to flexio_i2s_handle_t structure

void FLEXIO_I2S_TransferRxHandleIRQ(void *i2sBase, void *i2sHandle)

Rx interrupt handler.

Parameters

- i2sBase – Pointer to FLEXIO_I2S_Type structure.
- i2sHandle – Pointer to flexio_i2s_handle_t structure.

FSL_FLEXIO_I2S_DRIVER_VERSION

FlexIO I2S driver version 2.2.2.

FlexIO I2S transfer status.

Values:

enumerator kStatus_FLEXIO_I2S_Idle

FlexIO I2S is in idle state

enumerator kStatus_FLEXIO_I2S_TxBusy

FlexIO I2S Tx is busy

enumerator kStatus_FLEXIO_I2S_RxBusy

FlexIO I2S Tx is busy

enumerator kStatus_FLEXIO_I2S_Error

FlexIO I2S error occurred

enumerator kStatus_FLEXIO_I2S_QueueFull

FlexIO I2S transfer queue is full.

enumerator kStatus_FLEXIO_I2S_Timeout

FlexIO I2S timeout polling status flags.

enum _flexio_i2s_master_slave

Master or slave mode.

Values:

enumerator kFLEXIO_I2S_Master

Master mode

enumerator kFLEXIO_I2S_Slave

Slave mode

_flexio_i2s_interrupt_enable Define FlexIO FlexIO I2S interrupt mask.

Values:

enumerator kFLEXIO_I2S_TxDataRegEmptyInterruptEnable
Transmit buffer empty interrupt enable.

enumerator kFLEXIO_I2S_RxDataRegFullInterruptEnable
Receive buffer full interrupt enable.

_flexio_i2s_status_flags Define FlexIO FlexIO I2S status mask.

Values:

enumerator kFLEXIO_I2S_TxDataRegEmptyFlag
Transmit buffer empty flag.

enumerator kFLEXIO_I2S_RxDataRegFullFlag
Receive buffer full flag.

enum _flexio_i2s_sample_rate
Audio sample rate.

Values:

enumerator kFLEXIO_I2S_SampleRate8KHz
Sample rate 8000Hz

enumerator kFLEXIO_I2S_SampleRate11025Hz
Sample rate 11025Hz

enumerator kFLEXIO_I2S_SampleRate12KHz
Sample rate 12000Hz

enumerator kFLEXIO_I2S_SampleRate16KHz
Sample rate 16000Hz

enumerator kFLEXIO_I2S_SampleRate22050Hz
Sample rate 22050Hz

enumerator kFLEXIO_I2S_SampleRate24KHz
Sample rate 24000Hz

enumerator kFLEXIO_I2S_SampleRate32KHz
Sample rate 32000Hz

enumerator kFLEXIO_I2S_SampleRate44100Hz
Sample rate 44100Hz

enumerator kFLEXIO_I2S_SampleRate48KHz
Sample rate 48000Hz

enumerator kFLEXIO_I2S_SampleRate96KHz
Sample rate 96000Hz

enum _flexio_i2s_word_width
Audio word width.
Values:

enumerator kFLEXIO_I2S_WordWidth8bits
Audio data width 8 bits

enumerator kFLEXIO_I2S_WordWidth16bits
Audio data width 16 bits

enumerator kFLEXIO_I2S_WordWidth24bits
Audio data width 24 bits

enumerator kFLEXIO_I2S_WordWidth32bits
Audio data width 32 bits

typedef struct *_flexio_i2s_type* FLEXIO_I2S_Type
Define FlexIO I2S access structure typedef.

typedef enum *_flexio_i2s_master_slave* flexio_i2s_master_slave_t
Master or slave mode.

typedef struct *_flexio_i2s_config* flexio_i2s_config_t
FlexIO I2S configure structure.

typedef struct *_flexio_i2s_format* flexio_i2s_format_t
FlexIO I2S audio format, FlexIO I2S only support the same format in Tx and Rx.

typedef enum *_flexio_i2s_sample_rate* flexio_i2s_sample_rate_t
Audio sample rate.

typedef enum *_flexio_i2s_word_width* flexio_i2s_word_width_t
Audio word width.

typedef struct *_flexio_i2s_transfer* flexio_i2s_transfer_t
Define FlexIO I2S transfer structure.

typedef struct *_flexio_i2s_handle* flexio_i2s_handle_t

typedef void (*flexio_i2s_callback_t)(*FLEXIO_I2S_Type* *base, *flexio_i2s_handle_t* *handle, *status_t* status, void *userData)
FlexIO I2S xfer callback prototype.

I2S_RETRY_TIMES
Retry times for waiting flag.

FLEXIO_I2S_XFER_QUEUE_SIZE
FlexIO I2S transfer queue size, user can refine it according to use case.

struct _flexio_i2s_type
#include <fsl_flexio_i2s.h> Define FlexIO I2S access structure typedef.

Public Members

FLEXIO_Type *flexioBase
FlexIO base pointer

uint8_t txPinIndex
Tx data pin index in FlexIO pins

uint8_t rxPinIndex
Rx data pin index

uint8_t bclkPinIndex
Bit clock pin index

uint8_t fsPinIndex
Frame sync pin index

uint8_t txShifterIndex
Tx data shifter index

uint8_t rxShifterIndex
Rx data shifter index

uint8_t bclkTimerIndex
Bit clock timer index

uint8_t fsTimerIndex
Frame sync timer index

struct _flexio_i2s_config
#include <fsl_flexio_i2s.h> FlexIO I2S configure structure.

Public Members

bool enableI2S
Enable FlexIO I2S

flexio_i2s_master_slave_t masterSlave
Master or slave

flexio_pin_polarity_t txPinPolarity
Tx data pin polarity, active high or low

flexio_pin_polarity_t rxPinPolarity
Rx data pin polarity

flexio_pin_polarity_t bclkPinPolarity
Bit clock pin polarity

flexio_pin_polarity_t fsPinPolarity
Frame sync pin polarity

flexio_shifter_timer_polarity_t txTimerPolarity
Tx data valid on bclk rising or falling edge

flexio_shifter_timer_polarity_t rxTimerPolarity
Rx data valid on bclk rising or falling edge

struct __flexio_i2s_format
#include <fsl_flexio_i2s.h> FlexIO I2S audio format, FlexIO I2S only support the same format in Tx and Rx.

Public Members

uint8_t bitWidth
Bit width of audio data, always 8/16/24/32 bits

uint32_t sampleRate_Hz
Sample rate of the audio data

struct __flexio_i2s_transfer
#include <fsl_flexio_i2s.h> Define FlexIO I2S transfer structure.

Public Members

uint8_t *data
Data buffer start pointer

size_t dataSize
Bytes to be transferred.

struct __flexio_i2s_handle
#include <fsl_flexio_i2s.h> Define FlexIO I2S handle structure.

Public Members

uint32_t state
Internal state

flexio_i2s_callback_t callback
Callback function called at transfer event

void *userData
Callback parameter passed to callback function

uint8_t bitWidth
Bit width for transfer, 8/16/24/32bits

flexio_i2s_transfer_t queue[(4U)]
Transfer queue storing queued transfer

size_t transferSize[(4U)]
Data bytes need to transfer

volatile uint8_t queueUser
Index for user to queue transfer

volatile uint8_t queueDriver
Index for driver to get the transfer data and size

2.27 FlexIO MCU Interface LCD Driver

status_t FLEXIO_MCULCD_Init(*FLEXIO_MCULCD_Type* *base, *flexio_mculcd_config_t* *config, uint32_t srcClock_Hz)
Ungates the FlexIO clock, resets the FlexIO module, configures the FlexIO MCULCD hardware, and configures the FlexIO MCULCD with FlexIO MCULCD configuration. The configuration structure can be filled by the user, or be set with default values by the *FLEXIO_MCULCD_GetDefaultConfig*.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.
- config – Pointer to the flexio_mculcd_config_t structure.
- srcClock_Hz – FlexIO source clock in Hz.

Return values

- kStatus_Success – Initialization success.
- kStatus_InvalidArgument – Initialization failed because of invalid argument.

void FLEXIO_MCULCD_Deinit(*FLEXIO_MCULCD_Type* *base)
Resets the FLEXIO_MCULCD timer and shifter configuration.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type.

void FLEXIO_MCULCD_GetDefaultConfig(*flexio_mculcd_config_t* *config)

Gets the default configuration to configure the FlexIO MCULCD.

The default configuration value is:

```
config->enable = true;
config->enableInDoze = false;
config->enableInDebug = true;
config->enableFastAccess = true;
config->baudRate_Bps = 96000000U;
```

Parameters

- config – Pointer to the flexio_mculcd_config_t structure.

uint32_t FLEXIO_MCULCD_GetStatusFlags(*FLEXIO_MCULCD_Type* *base)

Gets FlexIO MCULCD status flags.

Note: Don't use this function with DMA APIs.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.

Returns

status flag; OR'ed value or the *_flexio_mculcd_status_flags*.

void FLEXIO_MCULCD_ClearStatusFlags(*FLEXIO_MCULCD_Type* *base, uint32_t mask)

Clears FlexIO MCULCD status flags.

Note: Don't use this function with DMA APIs.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.
- mask – Status to clear, it is the OR'ed value of *_flexio_mculcd_status_flags*.

void FLEXIO_MCULCD_EnableInterrupts(*FLEXIO_MCULCD_Type* *base, uint32_t mask)

Enables the FlexIO MCULCD interrupt.

This function enables the FlexIO MCULCD interrupt.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.
- mask – Interrupts to enable, it is the OR'ed value of *_flexio_mculcd_interrupt_enable*.

void FLEXIO_MCULCD_DisableInterrupts(*FLEXIO_MCULCD_Type* *base, uint32_t mask)

Disables the FlexIO MCULCD interrupt.

This function disables the FlexIO MCULCD interrupt.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.
- mask – Interrupts to disable, it is the OR'ed value of *_flexio_mculcd_interrupt_enable*.

static inline void FLEXIO_MCULCD_EnableTxDMA(*FLEXIO_MCULCD_Type* *base, bool enable)

Enables/disables the FlexIO MCULCD transmit DMA.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.
- enable – True means enable DMA, false means disable DMA.

static inline void FLEXIO_MCULCD_EnableRxDMA(*FLEXIO_MCULCD_Type* *base, bool enable)

Enables/disables the FlexIO MCULCD receive DMA.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.
- enable – True means enable DMA, false means disable DMA.

static inline uint32_t FLEXIO_MCULCD_GetTxDataRegisterAddress(*FLEXIO_MCULCD_Type* *base)

Gets the FlexIO MCULCD transmit data register address.

This function returns the MCULCD data register address, which is mainly used by DMA/eDMA.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.

Returns

FlexIO MCULCD transmit data register address.

static inline uint32_t FLEXIO_MCULCD_GetRxDataRegisterAddress(*FLEXIO_MCULCD_Type* *base)

Gets the FlexIO MCULCD receive data register address.

This function returns the MCULCD data register address, which is mainly used by DMA/eDMA.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.

Returns

FlexIO MCULCD receive data register address.

status_t FLEXIO_MCULCD_SetBaudRate(*FLEXIO_MCULCD_Type* *base, uint32_t baudRate_Bps, uint32_t srcClock_Hz)

Set desired baud rate.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.
- baudRate_Bps – Desired baud rate in bit-per-second for all data lines combined.
- srcClock_Hz – FLEXIO clock frequency in Hz.

Return values

- kStatus_Success – Set successfully.
- kStatus_InvalidArgument – Could not set the baud rate.

void FLEXIO_MCULCD_SetSingleBeatWriteConfig(*FLEXIO_MCULCD_Type* *base)

Configures the FLEXIO MCULCD to multiple beats write mode.

At the begining multiple beats write operation, the FLEXIO MCULCD is configured to multiple beats write mode using this function. After write operation, the configuration is cleared by *FLEXIO_MCULCD_ClearSingleBeatWriteConfig*.

Note: This is an internal used function, upper layer should not use.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type.

void FLEXIO_MCULCD_ClearSingleBeatWriteConfig(*FLEXIO_MCULCD_Type* *base)

Clear the FLEXIO MCULCD multiple beats write mode configuration.

Clear the write configuration set by *FLEXIO_MCULCD_SetSingleBeatWriteConfig*.

Note: This is an internal used function, upper layer should not use.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type.

void FLEXIO_MCULCD_SetSingleBeatReadConfig(*FLEXIO_MCULCD_Type* *base)

Configures the FLEXIO MCULCD to multiple beats read mode.

At the begining or multiple beats read operation, the FLEXIO MCULCD is configured to multiple beats read mode using this function. After read operation, the configuration is cleared by *FLEXIO_MCULCD_ClearSingleBeatReadConfig*.

Note: This is an internal used function, upper layer should not use.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type.

void FLEXIO_MCULCD_ClearSingleBeatReadConfig(*FLEXIO_MCULCD_Type* *base)

Clear the FLEXIO MCULCD multiple beats read mode configuration.

Clear the read configuration set by *FLEXIO_MCULCD_SetSingleBeatReadConfig*.

Note: This is an internal used function, upper layer should not use.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type.

void FLEXIO_MCULCD_SetMultiBeatsWriteConfig(*FLEXIO_MCULCD_Type* *base)

Configures the FLEXIO MCULCD to multiple beats write mode.

At the begining multiple beats write operation, the FLEXIO MCULCD is configured to multiple beats write mode using this function. After write operation, the configuration is cleared by FLEXIO_MCULCD_ClearMultBeatsWriteConfig.

Note: This is an internal used function, upper layer should not use.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type.

void FLEXIO_MCULCD_ClearMultiBeatsWriteConfig(*FLEXIO_MCULCD_Type* *base)

Clear the FLEXIO MCULCD multiple beats write mode configuration.

Clear the write configuration set by FLEXIO_MCULCD_SetMultBeatsWriteConfig.

Note: This is an internal used function, upper layer should not use.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type.

void FLEXIO_MCULCD_SetMultiBeatsReadConfig(*FLEXIO_MCULCD_Type* *base)

Configures the FLEXIO MCULCD to multiple beats read mode.

At the begining or multiple beats read operation, the FLEXIO MCULCD is configured to multiple beats read mode using this function. After read operation, the configuration is cleared by FLEXIO_MCULCD_ClearMultBeatsReadConfig.

Note: This is an internal used function, upper layer should not use.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type.

void FLEXIO_MCULCD_ClearMultiBeatsReadConfig(*FLEXIO_MCULCD_Type* *base)

Clear the FLEXIO MCULCD multiple beats read mode configuration.

Clear the read configuration set by FLEXIO_MCULCD_SetMultBeatsReadConfig.

Note: This is an internal used function, upper layer should not use.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type.

static inline void FLEXIO_MCULCD_Enable(*FLEXIO_MCULCD_Type* *base, bool enable)

Enables/disables the FlexIO MCULCD module operation.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type.
- enable – True to enable, false does not have any effect.

uint32_t FLEXIO_MCULCD_ReadData(*FLEXIO_MCULCD_Type* *base)

Read data from the FLEXIO MCULCD RX shifter buffer.

Read data from the RX shift buffer directly, it does no check whether the buffer is empty or not.

If the data bus width is 8-bit:

```
uint8_t value;
value = (uint8_t)FLEXIO_MCULCD_ReadData(base);
```

If the data bus width is 16-bit:

```
uint16_t value;
value = (uint16_t)FLEXIO_MCULCD_ReadData(base);
```

Note: This function returns the RX shifter buffer value (32-bit) directly. The return value should be converted according to data bus width.

Note: Don't use this function with DMA APIs.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.

Returns

The data read out.

static inline void FLEXIO_MCULCD_WriteData(*FLEXIO_MCULCD_Type* *base, uint32_t data)

Write data into the FLEXIO MCULCD TX shifter buffer.

Write data into the TX shift buffer directly, it does no check whether the buffer is full or not.

Note: Don't use this function with DMA APIs.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.
- data – The data to write.

static inline void FLEXIO_MCULCD_StartTransfer(*FLEXIO_MCULCD_Type* *base)

Assert the nCS to start transfer.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.

static inline void FLEXIO_MCULCD_StopTransfer(*FLEXIO_MCULCD_Type* *base)

De-assert the nCS to stop transfer.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.

void FLEXIO_MCULCD_WaitTransmitComplete(void)

Wait for transmit data send out finished.

Currently there is no effective method to wait for the data send out from the shiter, so here use a while loop to wait.

Note: This is an internal used function.

void FLEXIO_MCULCD_WriteCommandBlocking(*FLEXIO_MCULCD_Type* *base, uint32_t command)

Send command in blocking way.

This function sends the command and returns when the command has been sent out.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.
- command – The command to send.

void FLEXIO_MCULCD_WriteDataArrayBlocking(*FLEXIO_MCULCD_Type* *base, const void *data, size_t size)

Send data array in blocking way.

This function sends the data array and returns when the data sent out.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.
- data – The data array to send.
- size – How many bytes to write.

void FLEXIO_MCULCD_ReadDataArrayBlocking(*FLEXIO_MCULCD_Type* *base, void *data, size_t size)

Read data into array in blocking way.

This function reads the data into array and returns when the data read finished.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.
- data – The array to save the data.
- size – How many bytes to read.

void FLEXIO_MCULCD_WriteSameValueBlocking(*FLEXIO_MCULCD_Type* *base, uint32_t sameValue, size_t size)

Send the same value many times in blocking way.

This function sends the same value many times. It could be used to clear the LCD screen. If the data bus width is 8, this function will send LSB 8 bits of sameValue for size times. If the data bus is 16, this function will send LSB 16 bits of sameValue for size / 2 times.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.
- sameValue – The same value to send.
- size – How many bytes to send.

void FLEXIO_MCULCD_TransferBlocking(*FLEXIO_MCULCD_Type* *base, *flexio_mculcd_transfer_t* *xfer)

Performs a polling transfer.

Note: The API does not return until the transfer finished.

Parameters

- base – pointer to FLEXIO_MCULCD_Type structure.
- xfer – pointer to flexio_mculcd_transfer_t structure.

status_t FLEXIO_MCULCD_TransferCreateHandle(*FLEXIO_MCULCD_Type* *base, *flexio_mculcd_handle_t* *handle, *flexio_mculcd_transfer_callback_t* callback, void *userData)

Initializes the FlexIO MCULCD handle, which is used in transactional functions.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.
- handle – Pointer to the flexio_mculcd_handle_t structure to store the transfer state.
- callback – The callback function.
- userData – The parameter of the callback function.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_OutOfRange – The FlexIO type/handle/ISR table out of range.

status_t FLEXIO_MCULCD_TransferNonBlocking(*FLEXIO_MCULCD_Type* *base, *flexio_mculcd_handle_t* *handle, *flexio_mculcd_transfer_t* *xfer)

Transfer data using IRQ.

This function sends data using IRQ. This is a non-blocking function, which returns right away. When all data is sent out/received, the callback function is called.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.
- handle – Pointer to the flexio_mculcd_handle_t structure to store the transfer state.
- xfer – FlexIO MCULCD transfer structure. See *flexio_mculcd_transfer_t*.

Return values

- kStatus_Success – Successfully start a transfer.
- kStatus_InvalidArgument – Input argument is invalid.
- kStatus_FLEXIO_MCULCD_Busy – MCULCD is busy with another transfer.

void FLEXIO_MCULCD_TransferAbort(*FLEXIO_MCULCD_Type* *base, *flexio_mculcd_handle_t* *handle)

Aborts the data transfer, which used IRQ.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.
- handle – Pointer to the flexio_mculcd_handle_t structure to store the transfer state.

status_t FLEXIO_MCULCD_TransferGetCount(*FLEXIO_MCULCD_Type* *base, *flexio_mculcd_handle_t* *handle, size_t *count)

Gets the data transfer status which used IRQ.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.
- handle – Pointer to the flexio_mculcd_handle_t structure to store the transfer state.

- count – How many bytes transferred so far by the non-blocking transaction.

Return values

- kStatus_Success – Get the transferred count Successfully.
- kStatus_NoTransferInProgress – No transfer in process.

void FLEXIO_MCULCD_TransferHandleIRQ(void *base, void *handle)

FlexIO MCULCD IRQ handler function.

Parameters

- base – Pointer to the FLEXIO_MCULCD_Type structure.
- handle – Pointer to the flexio_mculcd_handle_t structure to store the transfer state.

FSL_FLEXIO_MCULCD_DRIVER_VERSION

FlexIO MCULCD driver version.

FlexIO LCD transfer status.

Values:

enumerator kStatus_FLEXIO_MCULCD_Idle

FlexIO LCD is idle.

enumerator kStatus_FLEXIO_MCULCD_Busy

FlexIO LCD is busy

enumerator kStatus_FLEXIO_MCULCD_Error

FlexIO LCD error occurred

enum _flexio_mculcd_pixel_format

Define FlexIO MCULCD pixel format.

Values:

enumerator kFLEXIO_MCULCD_RGB565

RGB565, 16-bit.

enumerator kFLEXIO_MCULCD_BGR565

BGR565, 16-bit.

enumerator kFLEXIO_MCULCD_RGB888

RGB888, 24-bit.

enumerator kFLEXIO_MCULCD_BGR888

BGR888, 24-bit.

enum _flexio_mculcd_bus

Define FlexIO MCULCD bus type.

Values:

enumerator kFLEXIO_MCULCD_8080
Using Intel 8080 bus.

enumerator kFLEXIO_MCULCD_6800
Using Motorola 6800 bus.

enum _flexio_mculcd_interrupt_enable
Define FlexIO MCULCD interrupt mask.

Values:

enumerator kFLEXIO_MCULCD_TxEmptyInterruptEnable
Transmit buffer empty interrupt enable.

enumerator kFLEXIO_MCULCD_RxFullInterruptEnable
Receive buffer full interrupt enable.

enum _flexio_mculcd_status_flags
Define FlexIO MCULCD status mask.

Values:

enumerator kFLEXIO_MCULCD_TxEmptyFlag
Transmit buffer empty flag.

enumerator kFLEXIO_MCULCD_RxFullFlag
Receive buffer full flag.

enum _flexio_mculcd_dma_enable
Define FlexIO MCULCD DMA mask.

Values:

enumerator kFLEXIO_MCULCD_TxDmaEnable
Tx DMA request source

enumerator kFLEXIO_MCULCD_RxDmaEnable
Rx DMA request source

enum _flexio_mculcd_transfer_mode
Transfer mode.

Values:

enumerator kFLEXIO_MCULCD_ReadArray
Read data into an array.

enumerator kFLEXIO_MCULCD_WriteArray
Write data from an array.

enumerator kFLEXIO_MCULCD_WriteSameValue
Write the same value many times.

typedef enum *_flexio_mculcd_pixel_format* flexio_mculcd_pixel_format_t

Define FlexIO MCULCD pixel format.

typedef enum *_flexio_mculcd_bus* flexio_mculcd_bus_t

Define FlexIO MCULCD bus type.

typedef void (*flexio_mculcd_pin_func_t)(bool set)

Function to set or clear the CS and RS pin.

typedef struct *_flexio_mculcd_type* FLEXIO_MCULCD_Type

Define FlexIO MCULCD access structure typedef.

typedef struct *_flexio_mculcd_config* flexio_mculcd_config_t

Define FlexIO MCULCD configuration structure.

typedef enum *_flexio_mculcd_transfer_mode* flexio_mculcd_transfer_mode_t

Transfer mode.

typedef struct *_flexio_mculcd_transfer* flexio_mculcd_transfer_t

Define FlexIO MCULCD transfer structure.

typedef struct *_flexio_mculcd_handle* flexio_mculcd_handle_t

typedef for flexio_mculcd_handle_t in advance.

typedef void (*flexio_mculcd_transfer_callback_t)(*FLEXIO_MCULCD_Type* *base, *flexio_mculcd_handle_t* *handle, *status_t* status, void *userData)

FlexIO MCULCD callback for finished transfer.

When transfer finished, the callback function is called and returns the status as kStatus_FLEXIO_MCULCD_Idle.

FLEXIO_MCULCD_WAIT_COMPLETE_TIME

The delay time to wait for FLEXIO transmit complete.

Currently there is no method to detect whether the data has been sent out from the shifter, so the driver use a software delay for this. When the data is written to shifter buffer, the driver call the delay function to wait for the data shift out. If this value is too small, then the last few bytes might be lost when writing data using interrupt method or DMA method.

FLEXIO_MCULCD_DATA_BUS_WIDTH

The data bus width, must be 8 or 16.

FLEXIO_MCULCD_LEGACY_GPIO_FUNC

Whether to use legacy GPIO functions to control the CS/RS/RDWR pin signal.

If using the legacy pin functions, there is no user defined argument passed to the function.

struct _flexio_mculcd_type

#include <fsl_flexio_mculcd.h> Define FlexIO MCULCD access structure typedef.

Public Members

FLEXIO_Type *flexioBase

FlexIO base pointer.

flexio_mculcd_bus_t busType

The bus type, 8080 or 6800.

uint8_t dataPinStartIndex

Start index of the data pin, the FlexIO pin dataPinStartIndex to (dataPinStartIndex + FLEXIO_MCULCD_DATA_BUS_WIDTH -1) will be used for data transfer. Only support data bus width 8 and 16.

uint8_t ENWRPinIndex

Pin select for WR(8080 mode), EN(6800 mode).

uint8_t RDPinIndex

Pin select for RD(8080 mode), not used in 6800 mode.

uint8_t txShifterStartIndex

Start index of shifters used for data write, it must be 0 or 4.

uint8_t txShifterEndIndex

End index of shifters used for data write.

uint8_t rxShifterStartIndex

Start index of shifters used for data read.

uint8_t rxShifterEndIndex

End index of shifters used for data read, it must be 3 or 7.

uint8_t timerIndex

Timer index used in FlexIO MCULCD.

flexio_mculcd_pin_func_t setCSPin

Function to set or clear the CS pin.

flexio_mculcd_pin_func_t setRSPin

Function to set or clear the RS pin.

flexio_mculcd_pin_func_t setRDWRPin

Function to set or clear the RD/WR pin, only used in 6800 mode.

struct __flexio_mculcd_config

#include <fsl_flexio_mculcd.h> Define FlexIO MCULCD configuration structure.

Public Members

bool enable

Enable/disable FlexIO MCULCD after configuration.

bool enableInDoze

Enable/disable FlexIO operation in doze mode.

bool enableInDebug

Enable/disable FlexIO operation in debug mode.

bool enableFastAccess

Enable/disable fast access to FlexIO registers, fast access requires the FlexIO clock to be at least twice the frequency of the bus clock.

uint32_t baudRate_Bps

Baud rate in bit-per-second for all data lines combined.

struct _flexio_mculcd_transfer

#include <fsl_flexio_mculcd.h> Define FlexIO MCULCD transfer structure.

Public Members

uint32_t command

Command to send.

uint32_t dataAddrOrSameValue

When sending the same value for many times, this is the value to send. When writing or reading array, this is the address of the data array.

size_t dataSize

How many bytes to transfer.

flexio_mculcd_transfer_mode_t mode

Transfer mode.

bool dataOnly

Send data only when tx without the command.

struct _flexio_mculcd_handle

#include <fsl_flexio_mculcd.h> Define FlexIO MCULCD handle structure.

Public Members

uint32_t dataAddrOrSameValue

When sending the same value for many times, this is the value to send. When writing or reading array, this is the address of the data array.

size_t dataCount
: Total count to be transferred.

volatile size_t remainingCount
: Remaining count to transfer.

volatile uint32_t state
: FlexIO MCULCD internal state.

flexio_mculcd_transfer_callback_t completionCallback
: FlexIO MCULCD transfer completed callback.

void *userData
: Callback parameter.

2.28 FlexIO SMARTDMA MCU Interface LCD Driver

status_t FLEXIO_MCULCD_TransferCreateHandleSMARTDMA(*FLEXIO_MCULCD_Type* *base, *flexio_mculcd_smartdma_handle_t* *handle, const *flexio_mculcd_smartdma_config_t* *config, *flexio_mculcd_smartdma_transfer_callback_t* callback, void *userData)

Initializes the FLEXO MCULCD master SMARTDMA handle.

This function initializes the FLEXO MCULCD master SMARTDMA handle which can be used for other FLEXO MCULCD transactional APIs. For a specified FLEXO MCULCD instance, call this API once to get the initialized handle.

Parameters

- base – Pointer to FLEXIO_MCULCD_Type structure.
- handle – Pointer to flexio_mculcd_smartdma_handle_t structure to store the transfer state.
- config – Pointer to the configuration.
- callback – MCULCD transfer complete callback, NULL means no callback.
- userData – callback function parameter.

Return values

kStatus_Success – Successfully create the handle.

status_t FLEXIO_MCULCD_TransferSMARTDMA(*FLEXIO_MCULCD_Type* *base, *flexio_mculcd_smartdma_handle_t* *handle, *flexio_mculcd_transfer_t* *xfer)

Performs a non-blocking FlexIO MCULCD transfer using SMARTDMA.

This function returns immediately after transfer initiates. Use the callback function to check whether the transfer is completed.

Parameters

- base – pointer to FLEXIO_MCULCD_Type structure.

- handle – pointer to flexio_mculcd_smartdma_handle_t structure to store the transfer state.
- xfer – Pointer to FlexIO MCULCD transfer structure.

Return values

- kStatus_Success – Successfully start a transfer.
- kStatus_InvalidArgument – Input argument is invalid.
- kStatus_FLEXIO_MCULCD_Busy – FlexIO MCULCD is not idle, it is running another transfer.

void FLEXIO_MCULCD_TransferAbortSMARTDMA(*FLEXIO_MCULCD_Type* *base, *flexio_mculcd_smartdma_handle_t* *handle)

Aborts a FlexIO MCULCD transfer using SMARTDMA.

Parameters

- base – pointer to FLEXIO_MCULCD_Type structure.
- handle – FlexIO MCULCD SMARTDMA handle pointer.

status_t FLEXIO_MCULCD_TransferGetCountSMARTDMA(*FLEXIO_MCULCD_Type* *base, *flexio_mculcd_smartdma_handle_t* *handle, size_t *count)

Gets the remaining bytes for FlexIO MCULCD SMARTDMA transfer.

Parameters

- base – pointer to FLEXIO_MCULCD_Type structure.
- handle – FlexIO MCULCD SMARTDMA handle pointer.
- count – Number of count transferred so far by the SMARTDMA transaction.

Return values

- kStatus_Success – Get the transferred count Successfully.
- kStatus_NoTransferInProgress – No transfer in process.

typedef struct *_flexio_mculcd_smartdma_handle* flexio_mculcd_smartdma_handle_t

typedef for flexio_mculcd_smartdma_handle_t in advance.

typedef void (*flexio_mculcd_smartdma_transfer_callback_t)(*FLEXIO_MCULCD_Type* *base, *flexio_mculcd_smartdma_handle_t* *handle, *status_t* status, void *userData)

FlexIO MCULCD master callback for transfer complete.

When transfer finished, the callback function is called and returns the status as kStatus_FLEXIO_MCULCD_Idle.

typedef struct *_flexio_mculcd_smartdma_config* flexio_mculcd_smartdma_config_t

FlexIO MCULCD SMARTDMA configuration.

FSL_FLEXIO_MCULCD_SMARTDMA_DRIVER_VERSION

FlexIO MCULCD SMARTDMA driver version.

FLEXIO_MCULCD_SMARTDMA_TX_LEN_ALIGN

SMARTDMA transfer size should be multiple of 64 bytes.

FLEXIO_MCULCD_SMARTDMA_TX_ADDR_ALIGN

SMARTDMA transfer memory address should be 4 byte aligned.

struct _flexio_mculcd_smartdma_handle

#include <fsl_flexio_mculcd_smartdma.h> FlexIO MCULCD SMARTDMA transfer handle, users should not touch the content of the handle.

Public Members

FLEXIO_MCULCD_Type *base

Pointer to the FLEXIO_MCULCD_Type.

size_t dataCount

Total count to be transferred.

uint32_t dataAddrOrSameValue

When sending the same value for many times, this is the value to send. When writing or reading array, this is the address of the data array.

size_t dataCountUsingEzh

Data transfered using SMARTDMA.

volatile size_t remainingCount

Remaining count to transfer.

volatile uint32_t state

FlexIO MCULCD driver internal state.

uint8_t smartdmaApi

The SMARTDMA API used during transfer.

bool needColorConvert

Need color convert or not.

uint8_t blockingXferBuffer[64U * 3 / 2]

Used for blocking method color space convet.

flexio_mculcd_smartdma_transfer_callback_t completionCallback

Callback for MCULCD SMARTDMA transfer

void *userData

User Data for MCULCD SMARTDMA callback

smartdma_flexio_mculcd_param_t smartdmaParam

SMARTDMA function parameters.

uint32_t smartdmaStack[1]

SMARTDMA function stack.

struct _flexio_mculcd_smartdma_config

#include <fsl_flexio_mculcd_smartdma.h> FlexIO MCULCD SMARTDMA configuration.

Public Members

flexio_mculcd_pixel_format_t inputPixelFormat

The pixel format in the frame buffer.

flexio_mculcd_pixel_format_t outputPixelFormat

The pixel format on the 8080/68k bus.

2.29 FlexIO SPI Driver

void FLEXIO_SPI_MasterInit(*FLEXIO_SPI_Type* *base, *flexio_spi_master_config_t* *masterConfig, uint32_t srcClock_Hz)

Ungates the FlexIO clock, resets the FlexIO module, configures the FlexIO SPI master hardware, and configures the FlexIO SPI with FlexIO SPI master configuration. The configuration structure can be filled by the user, or be set with default values by the *FLEXIO_SPI_MasterGetDefaultConfig()*.

Example

```
FLEXIO_SPI_Type spiDev = {
.flexioBase = FLEXIO,
.SDOPinIndex = 0,
.SDIPinIndex = 1,
.SCKPinIndex = 2,
.CSnPinIndex = 3,
.shifterIndex = {0,1},
.timerIndex = {0,1}
};
flexio_spi_master_config_t config = {
.enableMaster = true,
.enableInDoze = false,
.enableInDebug = true,
.enableFastAccess = false,
.baudRate_Bps = 500000,
.phase = kFLEXIO_SPI_ClockPhaseFirstEdge,
.direction = kFLEXIO_SPI_MsbFirst,
.dataMode = kFLEXIO_SPI_8BitMode
};
FLEXIO_SPI_MasterInit(&spiDev, &config, srcClock_Hz);
```

Note: 1.FlexIO SPI master only support CPOL = 0, which means clock inactive low. 2.For FlexIO SPI master, the input valid time is 1.5 clock cycles, for slave the output valid time is 2.5 clock cycles. So if FlexIO SPI master communicates with other spi IPs, the maximum baud rate is FlexIO clock frequency divided by 2*2=4. If FlexIO SPI master communicates with FlexIO SPI slave, the maximum baud rate is FlexIO clock frequency divided by (1.5+2.5)*2=8.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.

- masterConfig – Pointer to the flexio_spi_master_config_t structure.
- srcClock_Hz – FlexIO source clock in Hz.

void FLEXIO_SPI_MasterDeinit(*FLEXIO_SPI_Type* *base)

Resets the FlexIO SPI timer and shifter config.

Parameters

- base – Pointer to the FLEXIO_SPI_Type.

void FLEXIO_SPI_MasterGetDefaultConfig(*flexio_spi_master_config_t* *masterConfig)

Gets the default configuration to configure the FlexIO SPI master. The configuration can be used directly by calling the FLEXIO_SPI_MasterConfigure(). Example:

```
flexio_spi_master_config_t masterConfig;
FLEXIO_SPI_MasterGetDefaultConfig(&masterConfig);
```

Parameters

- masterConfig – Pointer to the flexio_spi_master_config_t structure.

void FLEXIO_SPI_SlaveInit(*FLEXIO_SPI_Type* *base, *flexio_spi_slave_config_t* *slaveConfig)

Ungates the FlexIO clock, resets the FlexIO module, configures the FlexIO SPI slave hardware configuration, and configures the FlexIO SPI with FlexIO SPI slave configuration. The configuration structure can be filled by the user, or be set with default values by the *FLEXIO_SPI_SlaveGetDefaultConfig()*.

Note: 1.Only one timer is needed in the FlexIO SPI slave. As a result, the second timer index is ignored. 2.FlexIO SPI slave only support CPOL = 0, which means clock inactive low. 3.For FlexIO SPI master, the input valid time is 1.5 clock cycles, for slave the output valid time is 2.5 clock cycles. So if FlexIO SPI slave communicates with other spi IPs, the maximum baud rate is FlexIO clock frequency divided by 3*2=6. If FlexIO SPI slave communicates with FlexIO SPI master, the maximum baud rate is FlexIO clock frequency divided by (1.5+2.5)*2=8. Example

```
FLEXIO_SPI_Type spiDev = {
.flexioBase = FLEXIO,
.SDOPinIndex = 0,
.SDIPinIndex = 1,
.SCKPinIndex = 2,
.CSnPinIndex = 3,
.shifterIndex = {0,1},
.timerIndex = {0}
};
flexio_spi_slave_config_t config = {
.enableSlave = true,
.enableInDoze = false,
.enableInDebug = true,
.enableFastAccess = false,
.phase = kFLEXIO_SPI_ClockPhaseFirstEdge,
.direction = kFLEXIO_SPI_MsbFirst,
.dataMode = kFLEXIO_SPI_8BitMode
};
FLEXIO_SPI_SlaveInit(&spiDev, &config);
```

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.

- slaveConfig – Pointer to the flexio_spi_slave_config_t structure.

void FLEXIO_SPI_SlaveDeinit(*FLEXIO_SPI_Type* *base)

Gates the FlexIO clock.

Parameters

- base – Pointer to the FLEXIO_SPI_Type.

void FLEXIO_SPI_SlaveGetDefaultConfig(*flexio_spi_slave_config_t* *slaveConfig)

Gets the default configuration to configure the FlexIO SPI slave. The configuration can be used directly for calling the FLEXIO_SPI_SlaveConfigure(). Example:

```
flexio_spi_slave_config_t slaveConfig;
FLEXIO_SPI_SlaveGetDefaultConfig(&slaveConfig);
```

Parameters

- slaveConfig – Pointer to the flexio_spi_slave_config_t structure.

uint32_t FLEXIO_SPI_GetStatusFlags(*FLEXIO_SPI_Type* *base)

Gets FlexIO SPI status flags.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.

Returns

status flag; Use the status flag to AND the following flag mask and get the status.

- kFLEXIO_SPI_TxEmptyFlag
- kFLEXIO_SPI_RxEmptyFlag

void FLEXIO_SPI_ClearStatusFlags(*FLEXIO_SPI_Type* *base, uint32_t mask)

Clears FlexIO SPI status flags.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- mask – status flag The parameter can be any combination of the following values:
  - kFLEXIO_SPI_TxEmptyFlag
  - kFLEXIO_SPI_RxEmptyFlag

void FLEXIO_SPI_EnableInterrupts(*FLEXIO_SPI_Type* *base, uint32_t mask)

Enables the FlexIO SPI interrupt.

This function enables the FlexIO SPI interrupt.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- mask – interrupt source. The parameter can be any combination of the following values:
  - kFLEXIO_SPI_RxFullInterruptEnable
  - kFLEXIO_SPI_TxEmptyInterruptEnable

void FLEXIO_SPI_DisableInterrupts(*FLEXIO_SPI_Type* *base, uint32_t mask)

Disables the FlexIO SPI interrupt.

This function disables the FlexIO SPI interrupt.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- mask – interrupt source The parameter can be any combination of the following values:
  - kFLEXIO_SPI_RxFullInterruptEnable
  - kFLEXIO_SPI_TxEmptyInterruptEnable

void FLEXIO_SPI_EnableDMA(*FLEXIO_SPI_Type* *base, uint32_t mask, bool enable)

Enables/disables the FlexIO SPI transmit DMA. This function enables/disables the FlexIO SPI Tx DMA, which means that asserting the kFLEXIO_SPI_TxEmptyFlag does/doesn't trigger the DMA request.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- mask – SPI DMA source.
- enable – True means enable DMA, false means disable DMA.

static inline uint32_t FLEXIO_SPI_GetTxDataRegisterAddress(*FLEXIO_SPI_Type* *base, *flexio_spi_shift_direction_t* direction)

Gets the FlexIO SPI transmit data register address for MSB first transfer.

This function returns the SPI data register address, which is mainly used by DMA/eDMA.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- direction – Shift direction of MSB first or LSB first.

Returns

FlexIO SPI transmit data register address.

static inline uint32_t FLEXIO_SPI_GetRxDataRegisterAddress(*FLEXIO_SPI_Type* *base, *flexio_spi_shift_direction_t* direction)

Gets the FlexIO SPI receive data register address for the MSB first transfer.

This function returns the SPI data register address, which is mainly used by DMA/eDMA.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- direction – Shift direction of MSB first or LSB first.

Returns

FlexIO SPI receive data register address.

static inline void FLEXIO_SPI_Enable(*FLEXIO_SPI_Type* *base, bool enable)

Enables/disables the FlexIO SPI module operation.

Parameters

- base – Pointer to the FLEXIO_SPI_Type.
- enable – True to enable, false does not have any effect.

void FLEXIO_SPI_MasterSetBaudRate(*FLEXIO_SPI_Type* *base, uint32_t baudRate_Bps, uint32_t srcClockHz)

Sets baud rate for the FlexIO SPI transfer, which is only used for the master.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- baudRate_Bps – Baud Rate needed in Hz.
- srcClockHz – SPI source clock frequency in Hz.

static inline void FLEXIO_SPI_WriteData(*FLEXIO_SPI_Type* *base, *flexio_spi_shift_direction_t* direction, uint32_t data)

Writes one byte of data, which is sent using the MSB method.

Note: This is a non-blocking API, which returns directly after the data is put into the data register but the data transfer is not finished on the bus. Ensure that the TxEmptyFlag is asserted before calling this API.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- direction – Shift direction of MSB first or LSB first.
- data – 8/16/32 bit data.

static inline uint32_t FLEXIO_SPI_ReadData(*FLEXIO_SPI_Type* *base, *flexio_spi_shift_direction_t* direction)

Reads 8 bit/16 bit data.

Note: This is a non-blocking API, which returns directly after the data is read from the data register. Ensure that the RxFullFlag is asserted before calling this API.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- direction – Shift direction of MSB first or LSB first.

Returns

8 bit/16 bit data received.

status_t FLEXIO_SPI_WriteBlocking(*FLEXIO_SPI_Type* *base, *flexio_spi_shift_direction_t* direction, const uint8_t *buffer, size_t size)

Sends a buffer of data bytes.

Note: This function blocks using the polling method until all bytes have been sent.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- direction – Shift direction of MSB first or LSB first.
- buffer – The data bytes to send.
- size – The number of data bytes to send.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_FLEXIO_SPI_Timeout – The transfer timed out and was aborted.

status_t FLEXIO_SPI_ReadBlocking(*FLEXIO_SPI_Type* *base, *flexio_spi_shift_direction_t* direction, uint8_t *buffer, size_t size)

Receives a buffer of bytes.

Note: This function blocks using the polling method until all bytes have been received.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- direction – Shift direction of MSB first or LSB first.
- buffer – The buffer to store the received bytes.
- size – The number of data bytes to be received.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_FLEXIO_SPI_Timeout – The transfer timed out and was aborted.

status_t FLEXIO_SPI_MasterTransferBlocking(*FLEXIO_SPI_Type* *base, *flexio_spi_transfer_t* *xfer)

Receives a buffer of bytes.

Note: This function blocks via polling until all bytes have been received.

Parameters

- base – pointer to FLEXIO_SPI_Type structure
- xfer – FlexIO SPI transfer structure, see *flexio_spi_transfer_t*.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_FLEXIO_SPI_Timeout – The transfer timed out and was aborted.

void FLEXIO_SPI_FlushShifters(*FLEXIO_SPI_Type* *base)

Flush tx/rx shifters.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.

status_t FLEXIO_SPI_MasterTransferCreateHandle(*FLEXIO_SPI_Type* *base, *flexio_spi_master_handle_t* *handle, *flexio_spi_master_transfer_callback_t* callback, void *userData)

Initializes the FlexIO SPI Master handle, which is used in transactional functions.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.

- handle – Pointer to the flexio_spi_master_handle_t structure to store the transfer state.
- callback – The callback function.
- userData – The parameter of the callback function.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_OutOfRange – The FlexIO type/handle/ISR table out of range.

status_t FLEXIO_SPI_MasterTransferNonBlocking(*FLEXIO_SPI_Type* *base, *flexio_spi_master_handle_t* *handle, *flexio_spi_transfer_t* *xfer)

Master transfer data using IRQ.

This function sends data using IRQ. This is a non-blocking function, which returns right away. When all data is sent out/received, the callback function is called.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- handle – Pointer to the flexio_spi_master_handle_t structure to store the transfer state.
- xfer – FlexIO SPI transfer structure. See *flexio_spi_transfer_t*.

Return values

- kStatus_Success – Successfully start a transfer.
- kStatus_InvalidArgument – Input argument is invalid.
- kStatus_FLEXIO_SPI_Busy – SPI is not idle, is running another transfer.

void FLEXIO_SPI_MasterTransferAbort(*FLEXIO_SPI_Type* *base, *flexio_spi_master_handle_t* *handle)

Aborts the master data transfer, which used IRQ.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- handle – Pointer to the flexio_spi_master_handle_t structure to store the transfer state.

status_t FLEXIO_SPI_MasterTransferGetCount(*FLEXIO_SPI_Type* *base, *flexio_spi_master_handle_t* *handle, size_t *count)

Gets the data transfer status which used IRQ.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- handle – Pointer to the flexio_spi_master_handle_t structure to store the transfer state.
- count – Number of bytes transferred so far by the non-blocking transaction.

Return values

- kStatus_InvalidArgument – count is Invalid.
- kStatus_Success – Successfully return the count.

void FLEXIO_SPI_MasterTransferHandleIRQ(void *spiType, void *spiHandle)

FlexIO SPI master IRQ handler function.

Parameters

- spiType – Pointer to the FLEXIO_SPI_Type structure.
- spiHandle – Pointer to the flexio_spi_master_handle_t structure to store the transfer state.

status_t FLEXIO_SPI_SlaveTransferCreateHandle(*FLEXIO_SPI_Type* *base, *flexio_spi_slave_handle_t* *handle, *flexio_spi_slave_transfer_callback_t* callback, void *userData)

Initializes the FlexIO SPI Slave handle, which is used in transactional functions.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- handle – Pointer to the flexio_spi_slave_handle_t structure to store the transfer state.
- callback – The callback function.
- userData – The parameter of the callback function.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_OutOfRange – The FlexIO type/handle/ISR table out of range.

status_t FLEXIO_SPI_SlaveTransferNonBlocking(*FLEXIO_SPI_Type* *base, *flexio_spi_slave_handle_t* *handle, *flexio_spi_transfer_t* *xfer)

Slave transfer data using IRQ.

This function sends data using IRQ. This is a non-blocking function, which returns right away. When all data is sent out/received, the callback function is called.

Parameters

- handle – Pointer to the flexio_spi_slave_handle_t structure to store the transfer state.
- base – Pointer to the FLEXIO_SPI_Type structure.
- xfer – FlexIO SPI transfer structure. See *flexio_spi_transfer_t*.

Return values

- kStatus_Success – Successfully start a transfer.
- kStatus_InvalidArgument – Input argument is invalid.
- kStatus_FLEXIO_SPI_Busy – SPI is not idle; it is running another transfer.

static inline void FLEXIO_SPI_SlaveTransferAbort(*FLEXIO_SPI_Type* *base, *flexio_spi_slave_handle_t* *handle)

Aborts the slave data transfer which used IRQ, share same API with master.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- handle – Pointer to the flexio_spi_slave_handle_t structure to store the transfer state.

static inline *status_t* FLEXIO_SPI_SlaveTransferGetCount(*FLEXIO_SPI_Type* *base, *flexio_spi_slave_handle_t* *handle, size_t *count)

Gets the data transfer status which used IRQ, share same API with master.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- handle – Pointer to the flexio_spi_slave_handle_t structure to store the transfer state.
- count – Number of bytes transferred so far by the non-blocking transaction.

Return values

- kStatus_InvalidArgument – count is Invalid.
- kStatus_Success – Successfully return the count.

void FLEXIO_SPI_SlaveTransferHandleIRQ(void *spiType, void *spiHandle)

FlexIO SPI slave IRQ handler function.

Parameters

- spiType – Pointer to the FLEXIO_SPI_Type structure.
- spiHandle – Pointer to the flexio_spi_slave_handle_t structure to store the transfer state.

FSL_FLEXIO_SPI_DRIVER_VERSION

FlexIO SPI driver version.

Error codes for the FlexIO SPI driver.

Values:

enumerator kStatus_FLEXIO_SPI_Busy

FlexIO SPI is busy.

enumerator kStatus_FLEXIO_SPI_Idle

SPI is idle

enumerator kStatus_FLEXIO_SPI_Error

FlexIO SPI error.

enumerator kStatus_FLEXIO_SPI_Timeout

FlexIO SPI timeout polling status flags.

enum _flexio_spi_clock_phase

FlexIO SPI clock phase configuration.

Values:

enumerator kFLEXIO_SPI_ClockPhaseFirstEdge

First edge on SPSCK occurs at the middle of the first cycle of a data transfer.

enumerator kFLEXIO_SPI_ClockPhaseSecondEdge
First edge on SPSCK occurs at the start of the first cycle of a data transfer.

enum _flexio_spi_shift_direction
FlexIO SPI data shifter direction options.
Values:

enumerator kFLEXIO_SPI_MsbFirst
Data transfers start with most significant bit.

enumerator kFLEXIO_SPI_LsbFirst
Data transfers start with least significant bit.

enum _flexio_spi_data_bitcount_mode
FlexIO SPI data length mode options.
Values:

enumerator kFLEXIO_SPI_8BitMode
8-bit data transmission mode.

enumerator kFLEXIO_SPI_16BitMode
16-bit data transmission mode.

enumerator kFLEXIO_SPI_32BitMode
32-bit data transmission mode.

enum _flexio_spi_interrupt_enable
Define FlexIO SPI interrupt mask.
Values:

enumerator kFLEXIO_SPI_TxEmptyInterruptEnable
Transmit buffer empty interrupt enable.

enumerator kFLEXIO_SPI_RxFullInterruptEnable
Receive buffer full interrupt enable.

enum _flexio_spi_status_flags
Define FlexIO SPI status mask.
Values:

enumerator kFLEXIO_SPI_TxBufferEmptyFlag
Transmit buffer empty flag.

enumerator kFLEXIO_SPI_RxBufferFullFlag
Receive buffer full flag.

enum _flexio_spi_dma_enable

Define FlexIO SPI DMA mask.

Values:

enumerator kFLEXIO_SPI_TxDmaEnable

Tx DMA request source

enumerator kFLEXIO_SPI_RxDmaEnable

Rx DMA request source

enumerator kFLEXIO_SPI_DmaAllEnable

All DMA request source

enum _flexio_spi_transfer_flags

Define FlexIO SPI transfer flags.

Note: Use kFLEXIO_SPI_csContinuous and one of the other flags to OR together to form the transfer flag.

Values:

enumerator kFLEXIO_SPI_8bitMsb

FlexIO SPI 8-bit MSB first

enumerator kFLEXIO_SPI_8bitLsb

FlexIO SPI 8-bit LSB first

enumerator kFLEXIO_SPI_16bitMsb

FlexIO SPI 16-bit MSB first

enumerator kFLEXIO_SPI_16bitLsb

FlexIO SPI 16-bit LSB first

enumerator kFLEXIO_SPI_32bitMsb

FlexIO SPI 32-bit MSB first

enumerator kFLEXIO_SPI_32bitLsb

FlexIO SPI 32-bit LSB first

enumerator kFLEXIO_SPI_csContinuous

Enable the CS signal continuous mode

typedef enum *_flexio_spi_clock_phase* flexio_spi_clock_phase_t

FlexIO SPI clock phase configuration.

typedef enum *_flexio_spi_shift_direction* flexio_spi_shift_direction_t

FlexIO SPI data shifter direction options.

typedef enum *_flexio_spi_data_bitcount_mode* flexio_spi_data_bitcount_mode_t

FlexIO SPI data length mode options.

typedef struct *_flexio_spi_type* FLEXIO_SPI_Type

Define FlexIO SPI access structure typedef.

typedef struct *_flexio_spi_master_config* flexio_spi_master_config_t

Define FlexIO SPI master configuration structure.

typedef struct *_flexio_spi_slave_config* flexio_spi_slave_config_t

Define FlexIO SPI slave configuration structure.

typedef struct *_flexio_spi_transfer* flexio_spi_transfer_t

Define FlexIO SPI transfer structure.

typedef struct *_flexio_spi_master_handle* flexio_spi_master_handle_t

typedef for flexio_spi_master_handle_t in advance.

typedef *flexio_spi_master_handle_t* flexio_spi_slave_handle_t

Slave handle is the same with master handle.

typedef void (*flexio_spi_master_transfer_callback_t)(*FLEXIO_SPI_Type* *base, *flexio_spi_master_handle_t* *handle, *status_t* status, void *userData)

FlexIO SPI master callback for finished transmit.

typedef void (*flexio_spi_slave_transfer_callback_t)(*FLEXIO_SPI_Type* *base, *flexio_spi_slave_handle_t* *handle, *status_t* status, void *userData)

FlexIO SPI slave callback for finished transmit.

FLEXIO_SPI_DUMMYDATA

FlexIO SPI dummy transfer data, the data is sent while txData is NULL.

SPI_RETRY_TIMES

Retry times for waiting flag.

FLEXIO_SPI_XFER_DATA_FORMAT(flag)

Get the transfer data format of width and bit order.

struct _flexio_spi_type

#include <fsl_flexio_spi.h> Define FlexIO SPI access structure typedef.

Public Members

FLEXIO_Type *flexioBase

FlexIO base pointer.

uint8_t SDOPinIndex

Pin select for data output. To set SDO pin in Hi-Z state, user needs to mux the pin as GPIO input and disable all pull up/down in application.

uint8_t SDIPinIndex
: Pin select for data input.

uint8_t SCKPinIndex
: Pin select for clock.

uint8_t CSnPinIndex
: Pin select for enable.

uint8_t shifterIndex[2]
: Shifter index used in FlexIO SPI.

uint8_t timerIndex[2]
: Timer index used in FlexIO SPI.

struct __flexio_spi_master_config
: *#include <fsl_flexio_spi.h>* Define FlexIO SPI master configuration structure.

Public Members

bool enableMaster
: Enable/disable FlexIO SPI master after configuration.

bool enableInDoze
: Enable/disable FlexIO operation in doze mode.

bool enableInDebug
: Enable/disable FlexIO operation in debug mode.

bool enableFastAccess
: Enable/disable fast access to FlexIO registers, fast access requires the FlexIO clock to be at least twice the frequency of the bus clock.

uint32_t baudRate_Bps
: Baud rate in Bps.

flexio_spi_clock_phase_t phase
: Clock phase.

flexio_spi_data_bitcount_mode_t dataMode
: 8bit or 16bit mode.

struct __flexio_spi_slave_config
: *#include <fsl_flexio_spi.h>* Define FlexIO SPI slave configuration structure.

Public Members

bool enableSlave
Enable/disable FlexIO SPI slave after configuration.

bool enableInDoze
Enable/disable FlexIO operation in doze mode.

bool enableInDebug
Enable/disable FlexIO operation in debug mode.

bool enableFastAccess
Enable/disable fast access to FlexIO registers, fast access requires the FlexIO clock to be at least twice the frequency of the bus clock.

flexio_spi_clock_phase_t phase
Clock phase.

flexio_spi_data_bitcount_mode_t dataMode
8bit or 16bit mode.

struct __flexio_spi_transfer
#include <fsl_flexio_spi.h> Define FlexIO SPI transfer structure.

Public Members

const uint8_t *txData
Send buffer.

uint8_t *rxData
Receive buffer.

size_t dataSize
Transfer bytes.

uint8_t flags
FlexIO SPI control flag, MSB first or LSB first.

struct __flexio_spi_master_handle
#include <fsl_flexio_spi.h> Define FlexIO SPI handle structure.

Public Members

const uint8_t *txData
Transfer buffer.

uint8_t *rxData
Receive buffer.

size_t transferSize
Total bytes to be transferred.

volatile size_t txRemainingBytes
Send data remaining in bytes.

volatile size_t rxRemainingBytes
Receive data remaining in bytes.

volatile uint32_t state
FlexIO SPI internal state.

uint8_t bytePerFrame
SPI mode, 2bytes or 1byte in a frame

flexio_spi_shift_direction_t direction
Shift direction.

flexio_spi_master_transfer_callback_t callback
FlexIO SPI callback.

void *userData
Callback parameter.

bool isCsContinuous
Is current transfer using CS continuous mode.

uint32_t timer1Cfg
TIMER1 TIMCFG regiser value backup.

2.30 Flexio_t-format

Error codes for the T_Format driver.

Values:

enumerator kStatus_FLEXIO_T_FORMAT_EncErr0_CountingErr
Transmitter is busy.

enumerator kStatus_FLEXIO_T_FORMAT_EncErr1_LogicOR
Encoder error: Logic-OR of Over-heat, Multi-turn error, Battery error and Battery alarm.

enumerator kStatus_FLEXIO_T_FORMAT_ComAlr0_ParityErr
Communication alarm: Parity error.

enumerator kStatus_FLEXIO_T_FORMAT_ComAlr1_DelimiterErr
Communication alarm: Delimiter error.

enumerator kStatus_FLEXIO_T_FORMAT_EncErr_OS
Over speed.

enumerator kStatus_FLEXIO_T_FORMAT_EncErr_FS
Full absolute status.

enumerator kStatus_FLEXIO_T_FORMAT_EncErr_CE
Countering error.

enumerator kStatus_FLEXIO_T_FORMAT_EncErr_OF
Countering overflow.

enumerator kStatus_FLEXIO_T_FORMAT_EncErr_OH
Over heat.

enumerator kStatus_FLEXIO_T_FORMAT_EncErr_ME
Multi-turn error.

enumerator kStatus_FLEXIO_T_FORMAT_EncErr_BE
Battery error.

enumerator kStatus_FLEXIO_T_FORMAT_EncErr_BA
Battery alarm.

enumerator kStatus_FLEXIO_T_FORMAT_FrameErr
Frame format error.

enumerator kStatus_FLEXIO_T_FORMAT_BaudrateNotSupport

enumerator kStatus_FLEXIO_T_FORMAT_Timeout
T_FORMAT times out.

enumerator kStatus_FLEXIO_T_FORMAT_TxBusy
Transmitter is busy.

enumerator kStatus_FLEXIO_T_FORMAT_RxBusy
Receiver is busy.

enumerator kStatus_FLEXIO_T_FORMAT_TxIdle
Transmitter is idle.

enumerator kStatus_FLEXIO_T_FORMAT_RxIdle
Receiver is idle.

enumerator kStatus_FLEXIO_T_FORMAT_RxRingBufferOverrun
A-format RX software ring buffer overrun.

enumerator kStatus_FLEXIO_T_FORMAT_RxHardwareOverrun
A-format RX receiver overrun.

enum _flexio_t_format_interrupt_enable
Define FlexIO T-format interrupt mask.
Values:

enumerator kFLEXIO_T_FORMAT_TxDataRegEmptyInterruptEnable
Transmit buffer empty interrupt enable.

enumerator kFLEXIO_T_FORMAT_RxDataRegFullInterruptEnable
Receive buffer full interrupt enable.

enum _flexio_t_format_flags
Values:

enumerator kFLEXIO_T_FORMAT_TxDataRegEmptyFlag
Transmit buffer empty flag.

enumerator kFLEXIO_T_FORMAT_RxDataRegFullFlag
Receive buffer full flag.

enumerator kFLEXIO_T_FORMAT_RxOverRunFlag
Receive buffer over run flag.

enum _flexio_t_format_user_modes
FlexIO T_FORMAT user modes.
Values:

enumerator kFLEXIO_T_FORMAT_USERMODE_ONESHOT
User mode is oneshot

enumerator kFLEXIO_T_FORMAT_USERMODE_SYNC
User mode is sync

typedef enum *_flexio_t_format_user_modes* flexio_t_format_user_modes_t
FlexIO T_FORMAT user modes.

typedef struct *_flexio_t_format_handle* flexio_t_format_handle_t

typedef struct *_flexio_t_format_type* FLEXIO_T_FORMAT_Type
Define FlexIO T_FORMAT access structure typedef.

typedef struct *_flexio_t_format_config* flexio_t_format_config_t
Define FlexIO T_FORMAT user configuration structure.

typedef struct *_flexio_t_format_transfer* flexio_t_format_transfer_t

Define FlexIO T-format transfer structure.

typedef void (*flexio_t_format_transfer_callback_t)(*FLEXIO_T_FORMAT_Type* *base, *flexio_t_format_handle_t* *handle, *status_t* status, void *userData)

FlexIO T-format transfer callback function.

static inline void FLEXIO_T_Format_WriteByte(*FLEXIO_T_FORMAT_Type* *base, const uint8_t *buffer)

Writes one byte of data.

Note: This is a non-blocking API, which returns directly after the data is put into the data register. Ensure that the TxEmptyFlag is asserted before calling this API.

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure.
- buffer – The data bytes to send.

static inline void FLEXIO_T_Format_ReadByte(*FLEXIO_T_FORMAT_Type* *base, uint8_t *buffer)

Reads one byte of data.

Note: This is a non-blocking API, which returns directly after the data is read from the data register. Ensure that the RxFullFlag is asserted before calling this API.

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure.
- buffer – The buffer to store the received bytes.

void FLEXIO_T_Format_Config_DR_length(*FLEXIO_T_FORMAT_Type* *base, uint32_t nFrames)

The duration of the high level of the RS485 DR Pin is set according to the number of frames.

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure
- nFrames – The number of frames (Each 8bit of data is one frame)

status_t FLEXIO_T_Format_Init(*FLEXIO_T_FORMAT_Type* *base, *flexio_t_format_config_t* *userConfig, uint32_t srcClock_Hz)

Ungates the FlexIO clock, resets the FlexIO module, configures the FlexIO T-Format hardware, and configures the FlexIO T-Format with FlexIO T-Format configuration. The configuration structure can be filled by the user, or be set with default values by the FLEXIO_T_FORMAT_GetDefaultConfig().

Example

```
FLEXIO_T_FORMAT_Type base = {
.flexioBase = FLEXIO,
.TxPinIndex = 0,
.RxPinIndex = 1,
.shifterIndex = {0,1},
```

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```
.timerIndex = {0,1}
};
flexio_t_format_config_t config = {
.enableInDoze = false,
.enableInDebug = true,
.enableFastAccess = false,
.baudRate_bps = 2500000
};
FLEXIO_T_Format_Init(&base, &config);
```

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure.
- userConfig – Pointer to the flexio_t_format_config_t structure.

Return values

kStatus_Success – Configuration success.

void FLEXIO_T_Format_Deinit(*FLEXIO_T_FORMAT_Type* *base)

Resets the FlexIO T-Format shifter and timer config.

note After calling this API, call the FLEXIO_T_Format_Init to use the FlexIO T_format module.

Parameters

- base – Pointer to FLEXIO_T_FORMAT_Type structure

void FLEXIO_T_Format_GetDefaultConfig(*flexio_t_format_config_t* *userConfig)

Gets the default configuration to configure the FlexIO T-format. The configuration can be used directly for calling the *FLEXIO_T_Format_Init()*. Example:

```
flexio_t_format_config_t config;
FLEXIO_T_Format_GetDefaultConfig(&userConfig);
```

Parameters

- userConfig – Pointer to the flexio_t_format_config_t structure.

void FLEXIO_T_Format_EnableInterrupts(*FLEXIO_T_FORMAT_Type* *base, uint32_t mask)

Enables the FlexIO T-format interrupt.

This function enables the FlexIO T-format interrupt.

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure.
- mask – Interrupt source.

void FLEXIO_T_Format_DisableInterrupts(*FLEXIO_T_FORMAT_Type* *base, uint32_t mask)

Disables the FlexIO T-format interrupt.

This function disables the FlexIO T-format interrupt.

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure.
- mask – Interrupt source.

uint32_t FLEXIO_T_Format_GetStatusFlags(*FLEXIO_T_FORMAT_Type* *base)

Gets the FlexIO T-format status flags.

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure.

Returns

FlexIO T-format status flags.

void FLEXIO_T_Format_ClearStatusFlags(*FLEXIO_T_FORMAT_Type* *base, uint32_t mask)

Clears the FlexIO T-format status flags.

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure.
- mask – Status flag. The parameter can be any combination of the following values: arg kFLEXIO_T_FORMAT_TxDataRegEmptyFlag arg kFLEXIO_T_FORMAT_RxDataRegFullFlag arg kFLEXIO_T_FORMAT_RxOverRunFlag

status_t FLEXIO_T_Format_WriteBlocking(*FLEXIO_T_FORMAT_Type* *base, const uint8_t *txData, size_t txSize)

Sends a buffer of data bytes.

note This function blocks using the polling method until all bytes have been sent.

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure.
- txData – The data bytes to send.
- txSize – The number of data bytes to send.

Return values

- kStatus_FLEXIO_T_FORMAT_Timeout – Transmission timed out and was aborted.
- kStatus_Success – Successfully wrote all data.

status_t FLEXIO_T_Format_ReadBlocking(*FLEXIO_T_FORMAT_Type* *base, uint8_t *rxData, size_t rxSize)

Receives a buffer of bytes.

note This function blocks using the polling method until all bytes have been received.

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure.
- rxData – The buffer to store the received bytes.
- rxSize – The number of data bytes to be received.

Return values

- kStatus_FLEXIO_T_FORMAT_Timeout – Transmission timed out and was aborted.
- kStatus_Success – Successfully received all data.

status_t FLEXIO_T_Format_TransferCreateHandle(*FLEXIO_T_FORMAT_Type* *base, *flexio_t_format_handle_t* *handle, *flexio_t_format_transfer_callback_t* callback, void *userData)

Initializes the T-format handle.

This function initializes the FlexIO T-format handle, which can be used for other FlexIO T-format transactional APIs. Call this API once to get the initialized handle.

The T-format driver supports the "background" receiving, which means that users can set up a RX ring buffer optionally. Data received is stored into the ring buffer even when the user doesn't call the *FLEXIO_T_Format_TransferReceiveNonBlocking()* API. If there is already data received in the ring buffer, users can get the received data from the ring buffer directly. The ring buffer is disabled if passing NULL as p ringBuffer.

Parameters

- base – to FLEXIO_T_FORMAT_Type structure.
- handle – Pointer to the flexio_t_format_handle_t structure to store the transfer state.
- callback – The callback function.
- userData – The parameter of the callback function.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_OutOfRange – The FlexIO type/handle/ISR table out of range.

void FLEXIO_T_Format_TransferStartRingBuffer(*FLEXIO_T_FORMAT_Type* *base, *flexio_t_format_handle_t* *handle, uint8_t *ringBuffer, size_t ringBufferSize)

Sets up the RX ring buffer.

This function sets up the RX ring buffer to a specific T-format handle.

When the RX ring buffer is used, data received is stored into the ring buffer even when the user doesn't call the T_Format_ReceiveNonBlocking() API. If there is already data received in the ring buffer, users can get the received data from the ring buffer directly.

note When using the RX ring buffer, one byte is reserved for internal use. In other words, if p ringBufferSize is 32, only 31 bytes are used for saving data.

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure.
- handle – Pointer to the flexio_t_format_handle_t structure to store the transfer state.
- ringBuffer – Start address of ring buffer for background receiving. Pass NULL to disable the ring buffer.
- ringBufferSize – Size of the ring buffer.

void FLEXIO_T_Format_TransferStopRingBuffer(*FLEXIO_T_FORMAT_Type* *base, *flexio_t_format_handle_t* *handle)

Aborts the background transfer and uninstalls the ring buffer.

This function aborts the background transfer and uninstalls the ring buffer.

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure.
- handle – Pointer to the flexio_t_format_handle_t structure to store the transfer state.

status_t FLEXIO_T_Format_TransferSendNonBlocking(*FLEXIO_T_FORMAT_Type* *base, *flexio_t_format_handle_t* *handle, *flexio_t_format_transfer_t* *xfer)

Transmits a buffer of data using the interrupt method.

This function sends data using an interrupt method. This is a non-blocking function, which returns directly without waiting for all data to be written to the TX register. When all data is written to the TX register in ISR, the FlexIO T-format driver calls the callback function and passes the ref kStatus_FLEXIO_T_FORMAT_TxIdle as status parameter.

note The kStatus_FLEXIO_T_FORMAT_TxIdle is passed to the upper layer when all data is written to the TX register. However, it does not ensure that all data is sent out.

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure.
- handle – Pointer to the flexio_t_format_handle_t structure to store the transfer state.
- xfer – FlexIO T-format transfer structure. See *flexio_t_format_transfer_t*.

Return values

- kStatus_Success – Successfully starts the data transmission.
- kStatus_T_FORMAT_TxBusy – Previous transmission still not finished, data not written to the TX register.

void FLEXIO_T_Format_TransferAbortSend(*FLEXIO_T_FORMAT_Type* *base, *flexio_t_format_handle_t* *handle)

Aborts the interrupt-driven data transmit.

This function aborts the interrupt-driven data sending. Get the remainHalfwords to find out how many half-words are still not sent out.

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure.
- handle – Pointer to the flexio_t_format_handle_t structure to store the transfer state.

status_t FLEXIO_T_Format_TransferGetSendCount(*FLEXIO_T_FORMAT_Type* *base, *flexio_t_format_handle_t* *handle, size_t *count)

Gets the number of bytes sent.

This function gets the number of bytes sent driven by interrupt.

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure.
- handle – Pointer to the flexio_t_format_handle_t structure to store the transfer state.
- count – Number of bytes sent so far by the non-blocking transaction.

Return values

- kStatus_NoTransferInProgress – transfer has finished or no transfer in progress.
- kStatus_Success – Successfully return the count.

status_t FLEXIO_T_Format_TransferReceiveNonBlocking(*FLEXIO_T_FORMAT_Type* *base, *flexio_t_format_handle_t* *handle, *flexio_t_format_transfer_t* *xfer, size_t *receivedBytes)

Receives a buffer of data using the interrupt method.

This function receives data using the interrupt method. This is a non-blocking function, which returns without waiting for all data to be received. If the RX ring buffer is used and not empty, the data in ring buffer is copied and the parameter p receivedBytes shows how many bytes are copied from the ring buffer. After copying, if the data in ring buffer is not enough to read, the receive request is saved by the T-format driver. When new data arrives, the receive request is serviced first. When all data is received, the T-format driver notifies the upper layer through a callback function and passes the status parameter ref kStatus_T_FORMAT_RxIdle. For example, if the upper layer needs 10 bytes but there are only 5 bytes in the ring buffer, the 5 bytes are copied to xfer->data. This function returns with the parameter p receivedBytes set to 5. For the last 5 bytes, newly arrived data is saved from the xfer->data[5]. When 5 bytes are received, the T-format driver notifies upper layer. If the RX ring buffer is not enabled, this function enables the RX and RX interrupt to receive data to xfer->data. When all data is received, the upper layer is notified.

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure.
- handle – Pointer to the flexio_t_format_handle_t structure to store the transfer state.
- xfer – T-format transfer structure. See *flexio_t_format_transfer_t*.
- receivedBytes – bytes received from the ring buffer directly.

Return values

- kStatus_Success – Successfully queue the transfer into the transmit queue.
- kStatus_FLEXIO_T_FORMAT_RxBusy – Previous receive request is not finished.

void FLEXIO_T_Format_TransferAbortReceive(*FLEXIO_T_FORMAT_Type* *base, *flexio_t_format_handle_t* *handle)

Aborts the receive data which was using IRQ.

This function aborts the receive data which was using IRQ.

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure.
- handle – Pointer to the flexio_t_format_handle_t structure to store the transfer state.

status_t FLEXIO_T_Format_TransferGetReceiveCount(*FLEXIO_T_FORMAT_Type* *base, *flexio_t_format_handle_t* *handle, size_t *count)

Gets the number of bytes received.

This function gets the number of bytes received driven by interrupt.

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure.
- handle – Pointer to the flexio_t_format_handle_t structure to store the transfer state.
- count – Number of bytes received so far by the non-blocking transaction.

Return values

- kStatus_NoTransferInProgress – transfer has finished or no transfer in progress.
- kStatus_Success – Successfully return the count.

status_t FLEXIO_T_Format_SendSyncReq(*FLEXIO_T_FORMAT_Type* *base, const uint8_t cf)

FlexIO T-format IRQ handler function.

Parameters

- base – Pointer to the FLEXIO_T_FORMAT_Type structure.
- cf – Sets commands to be sent in synchronous mode.

Returns

kStatus_Success

T_FORMAT_SINK_CODE_CF

The Sink code of the control field of T-format.

T_FORMAT_CF_MASK_SINK_CODE

The mask of the CF sink code.

T_FORMAT_CF_MASK_DATA_ID_CODE

The mask of the CF data ID code.

T_FORMAT_CF_MASK_ID_PARITY

The mask of the CF ID parity.

T_FORMAT_CF_DATA_ID_CODE(x)

Data ID code for the control field.

T_FORMAT_CF_ID_PARITY(x)

ID parity for the control field.

T_FORMAT_DATA_ID(code, parity)

The DATA ID Code of the T-format.

T_FORMAT_CF(DataID)

The control field of T-format.

T_FORMAT_CF_GET_ABS

List of the control field value.

T_FORMAT_CF_GET_ABM

T_FORMAT_CF_GET_ENCID

T_FORMAT_CF_GET_ALL

T_FORMAT_CF_RESET_ALL_ERROR

T_FORMAT_CF_RESET_ABS

T_FORMAT_CF_RESET_ABM_ERROR

T_FORMAT_CF_EEPROM_WRITE

T_FORMAT_CF_EEPROM_READOUT

T_FORMAT_ALMC_MASK_OVER_SPEED
: The mask bit of ALMC(Encoder error)

T_FORMAT_ALMC_MASK_FULL_ABSOLUTE_STATUS

T_FORMAT_ALMC_MASK_COUNTING_ERROR

T_FORMAT_ALMC_MASK_COUNTER_OVERFLOW

T_FORMAT_ALMC_MASK_OVERHEAT

T_FORMAT_ALMC_MASK_MULTITURN_ERROR

T_FORMAT_ALMC_MASK_BATTERY_ERROR

T_FORMAT_ALMC_MASK_BATTERY_ALARM

T_FORMAT_SF_MASK_ENCODER_ERROR
: The mask of the SF encoder error.

T_FORMAT_SF_MASK_COMMUNICATION_ALARM
: The mask of the SF communication alarm.

T_FORMAT_SF_GET_ENCODER_ERROR(x)
: Get the SF encoder error.

T_FORMAT_SF_GET_COMMUNICATION_ALARM(x)
: Get the SF communication alarm.

T_FORMAT_ADF_MASK_ADDRESS
: The mask of the ADF address.

T_FORMAT_SF_MASK_BUSY_STATUS
: The mask of the ADF busy status.

T_FORMAT_CRC_POLYNOMIAL
: The CRC polynomial.

T_FORMAT_ABS_BYTE
: The number of the byte in the received data.

T_FORMAT_ABM_BYTE

T_FORMAT_ENCODER_ID_BYTE

T_FORMAT_ALL_INFO_BYTE

T_FORMAT_EEPROM_BYTE

T_FORMAT_OVER_HEAT_NOT_CAUSE
: Do not cause Over-heat.

T_FORMAT_OVER_HEAT_TEMPERATURE(x)

T_FORMAT_TIMER_TX_INDEX

T_FORMAT_TIMER_RX_INDEX

T_FORMAT_TIMER_DR_INDEX

FSL_FLEXIO_T_FORMAT_DRIVER_VERSION
: FlexIO T_Format driver version.

T_FORMAT_RETRY_TIMES
: Retry times for waiting flag.

T_FORMAT_ENCODER_MAX_NUM
: Maximum number of encoders on an T-format bus.

T_FORMAT_BITS_PER_FRAME_DATA
: The number of bits per frame without start and stop bits.

T_FORMAT_BITS_PER_FRAME_WHOLE
: The number of bits per frame with start and stop bits.

T_FORMAT_TIMER_COMPARE_VALUE(cmp)
: Calculate the value of the FlexIO timer compare register.

FLEXIO_Type *flexioBase
: FlexIO base pointer.

flexio_t_format_handle_t *hanlde

uint16_t timerDiv
: srcClock_Hz / baudRate_bps

uint16_t TxDR_Offset
: The offset between Tx and DR pins

uint16_t interval
: Interval between frames

uint8_t TxPinIndex
: Pin select for T_FORMAT_Tx.

uint8_t RxPinIndex
: Pin select for T_FORMAT_Rx.

uint8_t DRPinIndex
: Pin select for T_FORMAT_DR.

uint8_t shifterIndex[2]
: Shifter index used in FlexIO T_FORMAT.

uint8_t timerIndex[3]
: Timer index used in FlexIO T_FORMAT.

uint8_t triggerIn
: Trigger signal for sync mode.

bool enableT_Format
: Enable/disable FlexIO T_FORMAT TX & RX.

bool enableInDoze
: Enable/disable FlexIO operation in doze mode

bool enableInDebug
: Enable/disable FlexIO operation in debug mode

bool enableFastAccess
: Enable/disable fast access to FlexIO registers, fast access requires the FlexIO clock to be at least twice the frequency of the bus clock.

uint8_t userMode

uint8_t *data
: The buffer of data to be transfer.

uint8_t *rxData
: The buffer to receive data.

const uint8_t *txData
: The buffer of data to be sent.

union _flexio_t_format_transfer

size_t dataSize
: Transfer size

const uint8_t *volatile txData
: Address of remaining data to send.

volatile size_t txDataSize
: Size of the remaining data to send.

uint8_t *volatile rxData
: Address of remaining data to receive.

volatile size_t rxDataSize
: Size of the remaining data to receive.

size_t txDataSizeAll
: Total bytes to be sent.

size_t rxDataSizeAll
: Total bytes to be received.

uint8_t *rxRingBuffer
: Start address of the receiver ring buffer.

size_t rxRingBufferSize
: Size of the ring buffer.

volatile uint16_t rxRingBufferHead
: Index for the driver to store received data into ring buffer.

volatile uint16_t rxRingBufferTail
: Index for the user to get data from the ring buffer.

flexio_t_format_transfer_callback_t callback
: Callback function.

void *userData
: A-format callback function parameter.

volatile uint8_t txState
: TX transfer state.

volatile uint8_t rxState
: RX transfer state

struct __flexio_t_format_type
: *#include <fsl_flexio_t-format.h>* Define FlexIO T_FORMAT access structure typedef.

struct __flexio_t_format_config
: *#include <fsl_flexio_t-format.h>* Define FlexIO T_FORMAT user configuration structure.

struct __flexio_t_format_transfer
: *#include <fsl_flexio_t-format.h>* Define FlexIO T-format transfer structure.

struct __flexio_t_format_handle
: *#include <fsl_flexio_t-format.h>* Define FLEXIO T-format handle structure.

union ___unnamed94___

Public Members

uint8_t *data
The buffer of data to be transfer.

uint8_t *rxData
The buffer to receive data.

const uint8_t *txData
The buffer of data to be sent.

2.31 FlexIO UART Driver

status_t FLEXIO_UART_Init(*FLEXIO_UART_Type* *base, const *flexio_uart_config_t* *userConfig, uint32_t srcClock_Hz)

Ungates the FlexIO clock, resets the FlexIO module, configures FlexIO UART hardware, and configures the FlexIO UART with FlexIO UART configuration. The configuration structure can be filled by the user or be set with default values by *FLEXIO_UART_GetDefaultConfig()*.

Example

```
FLEXIO_UART_Type base = {
.flexioBase = FLEXIO,
.TxPinIndex = 0,
.RxPinIndex = 1,
.shifterIndex = {0,1},
.timerIndex = {0,1}
};
flexio_uart_config_t config = {
.enableInDoze = false,
.enableInDebug = true,
.enableFastAccess = false,
.baudRate_Bps = 115200U,
.bitCountPerChar = 8
};
FLEXIO_UART_Init(base, &config, srcClock_Hz);
```

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- userConfig – Pointer to the flexio_uart_config_t structure.
- srcClock_Hz – FlexIO source clock in Hz.

Return values

- kStatus_Success – Configuration success.
- kStatus_FLEXIO_UART_BaudrateNotSupport – Baudrate is not supported for current clock source frequency.

void FLEXIO_UART_Deinit(*FLEXIO_UART_Type* *base)

Resets the FlexIO UART shifter and timer config.

Note: After calling this API, call the FLEXO_UART_Init to use the FlexIO UART module.

Parameters

- base – Pointer to FLEXIO_UART_Type structure

void FLEXIO_UART_GetDefaultConfig(*flexio_uart_config_t* *userConfig)

Gets the default configuration to configure the FlexIO UART. The configuration can be used directly for calling the *FLEXIO_UART_Init()*. Example:

```
flexio_uart_config_t config;
FLEXIO_UART_GetDefaultConfig(&userConfig);
```

Parameters

- userConfig – Pointer to the flexio_uart_config_t structure.

uint32_t FLEXIO_UART_GetStatusFlags(*FLEXIO_UART_Type* *base)

Gets the FlexIO UART status flags.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.

Returns

FlexIO UART status flags.

void FLEXIO_UART_ClearStatusFlags(*FLEXIO_UART_Type* *base, uint32_t mask)

Gets the FlexIO UART status flags.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- mask – Status flag. The parameter can be any combination of the following values:
  - kFLEXIO_UART_TxDataRegEmptyFlag
  - kFLEXIO_UART_RxEmptyFlag
  - kFLEXIO_UART_RxOverRunFlag

void FLEXIO_UART_EnableInterrupts(*FLEXIO_UART_Type* *base, uint32_t mask)

Enables the FlexIO UART interrupt.

This function enables the FlexIO UART interrupt.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- mask – Interrupt source.

void FLEXIO_UART_DisableInterrupts(*FLEXIO_UART_Type* *base, uint32_t mask)

Disables the FlexIO UART interrupt.

This function disables the FlexIO UART interrupt.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- mask – Interrupt source.

static inline uint32_t FLEXIO_UART_GetTxDataRegisterAddress(*FLEXIO_UART_Type* *base)

Gets the FlexIO UARt transmit data register address.

This function returns the UART data register address, which is mainly used by DMA/eDMA.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.

Returns

FlexIO UART transmit data register address.

static inline uint32_t FLEXIO_UART_GetRxDataRegisterAddress(*FLEXIO_UART_Type* *base)

Gets the FlexIO UART receive data register address.

This function returns the UART data register address, which is mainly used by DMA/eDMA.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.

Returns

FlexIO UART receive data register address.

static inline void FLEXIO_UART_EnableTxDMA(*FLEXIO_UART_Type* *base, bool enable)

Enables/disables the FlexIO UART transmit DMA. This function enables/disables the FlexIO UART Tx DMA, which means asserting the kFLEXIO_UART_TxDataRegEmptyFlag does/doesn't trigger the DMA request.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- enable – True to enable, false to disable.

static inline void FLEXIO_UART_EnableRxDMA(*FLEXIO_UART_Type* *base, bool enable)

Enables/disables the FlexIO UART receive DMA. This function enables/disables the FlexIO UART Rx DMA, which means asserting kFLEXIO_UART_RxDataRegFullFlag does/doesn't trigger the DMA request.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- enable – True to enable, false to disable.

static inline void FLEXIO_UART_Enable(*FLEXIO_UART_Type* *base, bool enable)

Enables/disables the FlexIO UART module operation.

Parameters

- base – Pointer to the FLEXIO_UART_Type.
- enable – True to enable, false does not have any effect.

static inline void FLEXIO_UART_WriteByte(*FLEXIO_UART_Type* *base, const uint8_t *buffer)

Writes one byte of data.

Note: This is a non-blocking API, which returns directly after the data is put into the data register. Ensure that the TxEmptyFlag is asserted before calling this API.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- buffer – The data bytes to send.

static inline void FLEXIO_UART_ReadByte(*FLEXIO_UART_Type* *base, uint8_t *buffer)

Reads one byte of data.

Note: This is a non-blocking API, which returns directly after the data is read from the data register. Ensure that the RxFullFlag is asserted before calling this API.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- buffer – The buffer to store the received bytes.

status_t FLEXIO_UART_WriteBlocking(*FLEXIO_UART_Type* *base, const uint8_t *txData, size_t txSize)

Sends a buffer of data bytes.

Note: This function blocks using the polling method until all bytes have been sent.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- txData – The data bytes to send.
- txSize – The number of data bytes to send.

Return values

- kStatus_FLEXIO_UART_Timeout – Transmission timed out and was aborted.
- kStatus_Success – Successfully wrote all data.

status_t FLEXIO_UART_ReadBlocking(*FLEXIO_UART_Type* *base, uint8_t *rxData, size_t rxSize)

Receives a buffer of bytes.

Note: This function blocks using the polling method until all bytes have been received.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- rxData – The buffer to store the received bytes.
- rxSize – The number of data bytes to be received.

Return values

- kStatus_FLEXIO_UART_Timeout – Transmission timed out and was aborted.
- kStatus_Success – Successfully received all data.

status_t FLEXIO_UART_TransferCreateHandle(*FLEXIO_UART_Type* *base, *flexio_uart_handle_t* *handle, *flexio_uart_transfer_callback_t* callback, void *userData)

Initializes the UART handle.

This function initializes the FlexIO UART handle, which can be used for other FlexIO UART transactional APIs. Call this API once to get the initialized handle.

The UART driver supports the "background" receiving, which means that users can set up a RX ring buffer optionally. Data received is stored into the ring buffer even when the user doesn't call the *FLEXIO_UART_TransferReceiveNonBlocking()* API. If there is already data received in the ring buffer, users can get the received data from the ring buffer directly. The ring buffer is disabled if passing NULL as ringBuffer.

Parameters

- base – to FLEXIO_UART_Type structure.
- handle – Pointer to the flexio_uart_handle_t structure to store the transfer state.
- callback – The callback function.
- userData – The parameter of the callback function.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_OutOfRange – The FlexIO type/handle/ISR table out of range.

void FLEXIO_UART_TransferStartRingBuffer(*FLEXIO_UART_Type* *base, *flexio_uart_handle_t* *handle, uint8_t *ringBuffer, size_t ringBufferSize)

Sets up the RX ring buffer.

This function sets up the RX ring buffer to a specific UART handle.

When the RX ring buffer is used, data received is stored into the ring buffer even when the user doesn't call the UART_ReceiveNonBlocking() API. If there is already data received in the ring buffer, users can get the received data from the ring buffer directly.

Note: When using the RX ring buffer, one byte is reserved for internal use. In other words, if ringBufferSize is 32, only 31 bytes are used for saving data.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- handle – Pointer to the flexio_uart_handle_t structure to store the transfer state.
- ringBuffer – Start address of ring buffer for background receiving. Pass NULL to disable the ring buffer.
- ringBufferSize – Size of the ring buffer.

void FLEXIO_UART_TransferStopRingBuffer(*FLEXIO_UART_Type* *base, *flexio_uart_handle_t* *handle)

Aborts the background transfer and uninstalls the ring buffer.

This function aborts the background transfer and uninstalls the ring buffer.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.

- handle – Pointer to the flexio_uart_handle_t structure to store the transfer state.

status_t FLEXIO_UART_TransferSendNonBlocking(*FLEXIO_UART_Type* *base, *flexio_uart_handle_t* *handle, *flexio_uart_transfer_t* *xfer)

Transmits a buffer of data using the interrupt method.

This function sends data using an interrupt method. This is a non-blocking function, which returns directly without waiting for all data to be written to the TX register. When all data is written to the TX register in ISR, the FlexIO UART driver calls the callback function and passes the *kStatus_FLEXIO_UART_TxIdle* as status parameter.

Note: The kStatus_FLEXIO_UART_TxIdle is passed to the upper layer when all data is written to the TX register. However, it does not ensure that all data is sent out.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- handle – Pointer to the flexio_uart_handle_t structure to store the transfer state.
- xfer – FlexIO UART transfer structure. See *flexio_uart_transfer_t*.

Return values

- kStatus_Success – Successfully starts the data transmission.
- kStatus_UART_TxBusy – Previous transmission still not finished, data not written to the TX register.

void FLEXIO_UART_TransferAbortSend(*FLEXIO_UART_Type* *base, *flexio_uart_handle_t* *handle)

Aborts the interrupt-driven data transmit.

This function aborts the interrupt-driven data sending. Get the remainBytes to find out how many bytes are still not sent out.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- handle – Pointer to the flexio_uart_handle_t structure to store the transfer state.

status_t FLEXIO_UART_TransferGetSendCount(*FLEXIO_UART_Type* *base, *flexio_uart_handle_t* *handle, size_t *count)

Gets the number of bytes sent.

This function gets the number of bytes sent driven by interrupt.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- handle – Pointer to the flexio_uart_handle_t structure to store the transfer state.
- count – Number of bytes sent so far by the non-blocking transaction.

Return values

- kStatus_NoTransferInProgress – transfer has finished or no transfer in progress.

- kStatus_Success – Successfully return the count.

status_t FLEXIO_UART_TransferReceiveNonBlocking(*FLEXIO_UART_Type* *base, *flexio_uart_handle_t* *handle, *flexio_uart_transfer_t* *xfer, size_t *receivedBytes)

Receives a buffer of data using the interrupt method.

This function receives data using the interrupt method. This is a non-blocking function, which returns without waiting for all data to be received. If the RX ring buffer is used and not empty, the data in ring buffer is copied and the parameter receivedBytes shows how many bytes are copied from the ring buffer. After copying, if the data in ring buffer is not enough to read, the receive request is saved by the UART driver. When new data arrives, the receive request is serviced first. When all data is received, the UART driver notifies the upper layer through a callback function and passes the status parameter kStatus_UART_RxIdle. For example, if the upper layer needs 10 bytes but there are only 5 bytes in the ring buffer, the 5 bytes are copied to xfer->data. This function returns with the parameter receivedBytes set to 5. For the last 5 bytes, newly arrived data is saved from the xfer->data[5]. When 5 bytes are received, the UART driver notifies upper layer. If the RX ring buffer is not enabled, this function enables the RX and RX interrupt to receive data to xfer->data. When all data is received, the upper layer is notified.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- handle – Pointer to the flexio_uart_handle_t structure to store the transfer state.
- xfer – UART transfer structure. See *flexio_uart_transfer_t*.
- receivedBytes – Bytes received from the ring buffer directly.

Return values

- kStatus_Success – Successfully queue the transfer into the transmit queue.
- kStatus_FLEXIO_UART_RxBusy – Previous receive request is not finished.

void FLEXIO_UART_TransferAbortReceive(*FLEXIO_UART_Type* *base, *flexio_uart_handle_t* *handle)

Aborts the receive data which was using IRQ.

This function aborts the receive data which was using IRQ.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- handle – Pointer to the flexio_uart_handle_t structure to store the transfer state.

status_t FLEXIO_UART_TransferGetReceiveCount(*FLEXIO_UART_Type* *base, *flexio_uart_handle_t* *handle, size_t *count)

Gets the number of bytes received.

This function gets the number of bytes received driven by interrupt.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- handle – Pointer to the flexio_uart_handle_t structure to store the transfer state.
- count – Number of bytes received so far by the non-blocking transaction.

Return values

- kStatus_NoTransferInProgress – transfer has finished or no transfer in progress.
- kStatus_Success – Successfully return the count.

void FLEXIO_UART_TransferHandleIRQ(void *uartType, void *uartHandle)

FlexIO UART IRQ handler function.

This function processes the FlexIO UART transmit and receives the IRQ request.

Parameters

- uartType – Pointer to the FLEXIO_UART_Type structure.
- uartHandle – Pointer to the flexio_uart_handle_t structure to store the transfer state.

void FLEXIO_UART_FlushShifters(*FLEXIO_UART_Type* *base)

Flush tx/rx shifters.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.

FSL_FLEXIO_UART_DRIVER_VERSION

FlexIO UART driver version.

Error codes for the UART driver.

Values:

enumerator kStatus_FLEXIO_UART_TxBusy

Transmitter is busy.

enumerator kStatus_FLEXIO_UART_RxBusy

Receiver is busy.

enumerator kStatus_FLEXIO_UART_TxIdle

UART transmitter is idle.

enumerator kStatus_FLEXIO_UART_RxIdle

UART receiver is idle.

enumerator kStatus_FLEXIO_UART_ERROR

ERROR happens on UART.

enumerator kStatus_FLEXIO_UART_RxRingBufferOverrun

UART RX software ring buffer overrun.

enumerator kStatus_FLEXIO_UART_RxHardwareOverrun

UART RX receiver overrun.

enumerator kStatus_FLEXIO_UART_Timeout

UART times out.

enumerator kStatus_FLEXIO_UART_BaudrateNotSupport
Baudrate is not supported in current clock source

enum _flexio_uart_bit_count_per_char
FlexIO UART bit count per char.
Values:

enumerator kFLEXIO_UART_7BitsPerChar
7-bit data characters

enumerator kFLEXIO_UART_8BitsPerChar
8-bit data characters

enumerator kFLEXIO_UART_9BitsPerChar
9-bit data characters

enum _flexio_uart_interrupt_enable
Define FlexIO UART interrupt mask.
Values:

enumerator kFLEXIO_UART_TxDataRegEmptyInterruptEnable
Transmit buffer empty interrupt enable.

enumerator kFLEXIO_UART_RxDataRegFullInterruptEnable
Receive buffer full interrupt enable.

enum _flexio_uart_status_flags
Define FlexIO UART status mask.
Values:

enumerator kFLEXIO_UART_TxDataRegEmptyFlag
Transmit buffer empty flag.

enumerator kFLEXIO_UART_RxDataRegFullFlag
Receive buffer full flag.

enumerator kFLEXIO_UART_RxOverRunFlag
Receive buffer over run flag.

typedef enum *_flexio_uart_bit_count_per_char* flexio_uart_bit_count_per_char_t
FlexIO UART bit count per char.

typedef struct *_flexio_uart_type* FLEXIO_UART_Type
Define FlexIO UART access structure typedef.

typedef struct *_flexio_uart_config* flexio_uart_config_t
Define FlexIO UART user configuration structure.

typedef struct *_flexio_uart_transfer* flexio_uart_transfer_t

Define FlexIO UART transfer structure.

typedef struct *_flexio_uart_handle* flexio_uart_handle_t

typedef void (*flexio_uart_transfer_callback_t)(*FLEXIO_UART_Type* *base, *flexio_uart_handle_t* *handle, *status_t* status, void *userData)

FlexIO UART transfer callback function.

UART_RETRY_TIMES

Retry times for waiting flag.

struct _flexio_uart_type

#include <fsl_flexio_uart.h> Define FlexIO UART access structure typedef.

Public Members

FLEXIO_Type *flexioBase

FlexIO base pointer.

uint8_t TxPinIndex

Pin select for UART_Tx.

uint8_t RxPinIndex

Pin select for UART_Rx.

uint8_t shifterIndex[2]

Shifter index used in FlexIO UART.

uint8_t timerIndex[2]

Timer index used in FlexIO UART.

struct _flexio_uart_config

#include <fsl_flexio_uart.h> Define FlexIO UART user configuration structure.

Public Members

bool enableUart

Enable/disable FlexIO UART TX & RX.

bool enableInDoze

Enable/disable FlexIO operation in doze mode

bool enableInDebug

Enable/disable FlexIO operation in debug mode

bool enableFastAccess

Enable/disable fast access to FlexIO registers, fast access requires the FlexIO clock to be at least twice the frequency of the bus clock.

uint32_t baudRate_Bps

Baud rate in Bps.

flexio_uart_bit_count_per_char_t bitCountPerChar

number of bits, 7/8/9 -bit

struct __flexio_uart_transfer

#include <fsl_flexio_uart.h> Define FlexIO UART transfer structure.

Public Members

size_t dataSize

Transfer size

struct __flexio_uart_handle

#include <fsl_flexio_uart.h> Define FLEXIO UART handle structure.

Public Members

const uint8_t *volatile txData

Address of remaining data to send.

volatile size_t txDataSize

Size of the remaining data to send.

uint8_t *volatile rxData

Address of remaining data to receive.

volatile size_t rxDataSize

Size of the remaining data to receive.

size_t txDataSizeAll

Total bytes to be sent.

size_t rxDataSizeAll

Total bytes to be received.

uint8_t *rxRingBuffer

Start address of the receiver ring buffer.

size_t rxRingBufferSize

Size of the ring buffer.

volatile uint16_t rxRingBufferHead
Index for the driver to store received data into ring buffer.

volatile uint16_t rxRingBufferTail
Index for the user to get data from the ring buffer.

flexio_uart_transfer_callback_t callback
Callback function.

void *userData
UART callback function parameter.

volatile uint8_t txState
TX transfer state.

volatile uint8_t rxState
RX transfer state

union ___unnamed97___

Public Members

uint8_t *data
The buffer of data to be transfer.

uint8_t *rxData
The buffer to receive data.

const uint8_t *txData
The buffer of data to be sent.

2.32 FlexPWM: Enhanced Flex Pulse Width Modulator

void FLEXPWM_GetDefaultSubmoduleConfig(*flexpwm_submodule_config_t* *config)
Get default configuration for FlexPWM submodule.

This function initializes the FlexPWM submodule configuration structure with safe default values. The default configuration can be used directly or modified before calling *FLEXPWM_ConfigSubmodule()*.

Default values:

- Clock source: IPBus clock (kFLEXPWM_ClockSource_IPBusClock)
- Prescaler: Divide by 1 (no prescaling)
- Counter initial value: 0
- Counter modulo value: 0xFFFF (maximum range)
- Initialization source: Local sync
- Load mode: Opportunity (load at PWM reload opportunity)

- Load frequency: 0 (every PWM cycle)
- Half-cycle reload: Disabled
- Full-cycle reload: Enabled
- Reload source: Local reload
- Half-cycle value: 0
- Debug mode: Disabled (PWM stops in Debug mode)
- Wait mode: Disabled (PWM stops in Wait mode)

Parameters

- config – Pointer to the submodule configuration structure.

void FLEXPWM_ConfigSubmodule(PWM_Type *base, uint8_t submodule, const *flexpwm_submodule_config_t* *config)

Configure a FlexPWM submodule.

This function configures the basic parameters of a FlexPWM submodule, including:

- Clock source and prescaler (CTRL2[CLK_SEL], CTRL[PRSC])
- Counter initialization and modulo values (INIT, VAL1)
- Counter initialization source (CTRL2[INIT_SEL])
- Register reload mode, frequency, and timing (CTRL[LDMOD, LDFQ, HALF, FULL], CTRL2[RELOAD_SEL])
- Half-cycle reload point (VAL0)
- Debug and Wait mode behavior (CTRL2[DBGEN, WAITEN])

Note: Prerequisites:

- Call *FLEXPWM_Init()* before this function to enable the peripheral clock.

Note: Configuration write behavior:

- This function writes configuration values to buffered registers.
- The configuration does NOT take effect immediately.
- After calling this function, you must set MCTRL[LDOK] bit using a separate function to transfer buffered register values to active registers.
- The actual transfer timing depends on the configured reload mode and reload opportunities.

Note: This function does NOT:

- Set the MCTRL[LDOK] bit (you must call a separate LDOK function)
- Start the PWM counter (use a separate start API)
- Configure PWM waveform parameters (VAL2-VAL5, deadtime, polarity, etc.)
- Configure fault protection or capture functionality
- Configure FORCE_OUT behavior (use FLEXPWM_ConfigForceOut)

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- config – Pointer to the submodule configuration structure.

void FLEXPWM_ConfigPWM(PWM_Type *base, uint8_t submodule, const *flexpwm_pwm_config_t* *config)

Configure PWM output for a FlexPWM submodule.

This function configures the PWM output parameters for a FlexPWM submodule, including:

- Compare values (VAL2, VAL3, VAL4, VAL5)
- Output polarity (POLA, POLB)
- Initial values (PWM23_INIT, PWM45_INIT)
- Operating mode: independent or complementary (INDEP)
- Complementary mode source selection (MCTRL[IPOL]) - only in complementary mode

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Note: For complementary mode (complementary = true):

- Only the selected channel compare values (pwma if ipolSource=kFLEXPWM_IPOL_PWM23, or pwmb if ipolSource=kFLEXPWM_IPOL_PWM45) needs to be configured.
- But polarity still needs to be set for the complementary output to work correctly.
- The unselected channel will be ignored by the hardware.
- MCTRL[IPOL] will be set according to ipolSource parameter.

Note: For independent mode (complementary = false):

- Both pwma and pwmb must be fully configured.
- INDEP bit will be set to 1 in SMxCTRL2.
- MCTRL[IPOL] is ignored by the hardware in this mode.

Note: This function does NOT:

- Set the MCTRL[LDOK] bit (you must call a separate LDOK function)
- Trigger FORCE_OUT events (in complementary mode, MCTRL[IPOL] requires FORCE_OUT to take effect)
- Enable PWM_A Output or PWM_B Output (use a separate API to enable outputs)

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- config – Pointer to the PWM configuration structure.

void FLEXPWM_ConfigPWMChannelX(PWM_Type *base, uint8_t submodule, const *flexpwm_pwm_channel_config_t* *pwmx)

Configure PWM_X output for a FlexPWM submodule.

This function configures the PWM_X output parameters for a FlexPWM submodule, including:

- Compare values (VAL0, VAL1)
- Output polarity (POLX)
- Initial values (PWMX_INIT)

Note: When submodule works in local sync mode, PWM_X polarity is inverted, because VAL1 determines both counter modulo and PWM_X turn-off edge. VAL0 determines PWM_X turn-on edge. Recommend setting submodule counter works in master sync mode if you want to use the PWM_X output, then both VAL0 and VAL1 can be used to control PWM_X waveform shape and polarity is normal.

Note: This function does NOT:

- Set the MCTRL[LDOK] bit (you must call a separate LDOK function)
- Enable PWM_X Output (use a separate API to enable outputs)

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- pwmx – Pointer to the PWM_X configuration structure.

void FLEXPWM_GetDefaultForceOutConfig(*flexpwm_force_out_config_t* *config)

Get default configuration for force output.

This function initializes the force output configuration structure with safe default values. The default configuration can be used directly or modified before calling *FLEXPWM_ConfigForceOut()*.

Default values:

- FORCE_OUT trigger source: Local software force (kFLEXPWM_ForceOutputSource_LocalForce)
- Counter initialization on FORCE_OUT: Disabled (false)
- PWM_A source: Generated PWM signal (kFLEXPWM_ForcePwmSource_Generated)
- PWM_A software value: Logic 0 (false)
- PWM_B source: Generated PWM signal (kFLEXPWM_ForcePwmSource_Generated)
- PWM_B software value: Logic 0 (false)

Parameters

- config – Pointer to the force output configuration structure.

void FLEXPWM_ConfigForceOut(PWM_Type *base, uint8_t submodule, const *flexpwm_force_out_config_t* *config)

Configure FORCE_OUT for a FlexPWM submodule.

This function configures the FORCE_OUT event parameters for a FlexPWM submodule, including:

- FORCE_OUT trigger source (CTRL2[FORCE_SEL]): software, master, external, sync signals, etc.
- Counter initialization triggered by FORCE_OUT (CTRL2[FRCEN])
- PWM source selection for deadtime logic (DTSRCSEL[SMxSEL23/45]): generated, inverted, software-controlled, or external signals
- Software-controlled output values (SWCOUT[SMxOUT23/45]) when source is software-controlled

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Note: Configuration write behavior:

- This function performs read-modify-write operations on global registers (DTSRCSEL, SWCOUT) to protect other submodules' configurations.
- Register writes are immediate and take effect when the corresponding FORCE_OUT event occurs.
- SWCOUT and DTSRCSEL are NOT affected by MCTRL[LDOK]; they are independent double-buffered registers that update on FORCE_OUT events.

Note: FORCE_OUT event effects: When a FORCE_OUT event occurs, the following updated values take effect simultaneously:

- PWM source routing from DTSRCSEL
- Software-controlled output values from SWCOUT
- Counter may be reinitialized if FRCEN is enabled

Note: This function does NOT:

- Trigger FORCE_OUT events (DTSRCSEL and SWCOUT settings require FORCE_OUT event to take effect)

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- config – Pointer to the force output configuration structure.

void FLEXPWM_GetDefaultFaultConfig(*flexpwm_fault_config_t* *config)

Get default configuration for fault protection.

This function initializes the fault protection configuration structure with safe default values. The default configuration can be used directly or modified before calling *FLEXPWM_ConfigFaultProtection()*.

Default values:

- Fault Input Active Level (faultInputActiveLevel): Active high (true)
- Fault Clearing Mode (faultClearingMode): Automatic fault clearing

- Safety Mode (enableSafetyMode): Enabled (safe mode)
- Full Cycle Recovery (enableFullCycleRecovery): Enabled
- Half Cycle Recovery (enableHalfCycleRecovery): Disabled
- Combinational Path (enableCombinatorialPath): Enabled (allow combinational path for fastest response)

Parameters

- config – Pointer to the fault protection configuration structure.

void FLEXPWM_GetDefaultFaultSubmoduleConfig(*flexpwm_fault_submodule_config_t* *config)

Get default configuration for fault submodule protection.

This function initializes the fault submodule configuration structure with safe default values. The default configuration can be used directly or modified before calling *FLEXPWM_ConfigFaultSubmodule()*.

Default values:

- Disable Mask: All faults (0x0F) affect each output
- Output Behavior: High-Z (high impedance) for all outputs

For single-channel platforms: disableMask_ch0 = 0x0F For dual-channel platforms: disableMask_ch0 = 0x0F, disableMask_ch1 = 0x0F

Parameters

- config – Pointer to the fault submodule configuration structure.

void FLEXPWM_GetDefaultFaultFilterConfig(*flexpwm_fault_filter_config_t* *config)

Get default configuration for fault filter.

This function initializes the fault filter configuration structure with safe default values. The default configuration provides moderate debouncing suitable for typical applications.

Default values:

- Filter Period (FILT_PER): 0x08 (8 IPBus clock cycles)
- Filter Count (FILT_CNT): 0x04 (7 consecutive samples = 4+3)
- Glitch Stretching (GSTR): Enabled

Effective debounce window: ~56 IPBus clock cycles

Parameters

- config – Pointer to the fault filter configuration structure.

void FLEXPWM_ConfigFaultProtection(PWM_Type *base, uint8_t faultChannel, const *flexpwm_fault_config_t* *config, uint16_t faultMask)

Configure fault protection for a FlexPWM fault channel.

This function configures global fault protection parameters for one fault channel, including fault input active level, clearing mode, safety mode, and fault recovery timing.

Configuration details:

- Fault input active level (faultInputActiveLevel): Selects whether fault is triggered by high or low
- Fault clearing mode (faultClearingMode): Controls how and when PWM outputs are re-enabled
- Safety mode (enableSafetyMode): Adds extra requirement that fault input be de-asserted before re-enable

- Fault recovery timing (enableFullCycleRecovery, enableHalfCycleRecovery): Specifies during which PWM cycle phase outputs re-enable
- Combinational path (enableCombinatorialPath): Trades off response speed vs. latency

---

Note: Prerequisites:

- Call *FLEXPWM_Init()* before this function to enable the peripheral clock.

Note: Configuration applies to the entire fault channel (all submodules that reference it). For platforms with dual fault channels, call this function separately for each channel.

Note: For platforms with dual fault channels:

- faultChannel 0: Configures FAULT0-3 (FCTRL/FSTS/FFILT at offset 0x18C)
- faultChannel 1: Configures FAULT4-7 (FCTRL/FSTS/FFILT at offset 0x198)

Parameters

- base – FlexPWM peripheral base address.
- faultChannel – Fault channel number (0 or 1 for dual-channel platforms).
- config – Pointer to the fault protection configuration structure.
- faultMask – Fault input selection mask for the channel. Each bit corresponds to one fault input:
  - bit[0] = FAULT0 (or FAULT4 for channel 1)
  - bit[1] = FAULT1 (or FAULT5 for channel 1)
  - bit[2] = FAULT2 (or FAULT6 for channel 1)
  - bit[3] = FAULT3 (or FAULT7 for channel 1) Example: 0x05 = configure FAULT0 and FAULT2 with the same settings. Can use flexpwm_fault_mask_t enum values (kFLEXPWM_FaultMask_0/1/2/3) and OR them together for multiple faults: (kFLEXPWM_FaultMask_0 | kFLEXPWM_FaultMask_2) = 0x05.

void FLEXPWM_ConfigFaultSubmodule(PWM_Type *base, uint8_t submodule, const *flexpwm_fault_submodule_config_t* *config)

Configure fault submodule protection for a FlexPWM submodule.

This function configures fault-to-PWM-output mapping and output behavior for all three PWM outputs (PWM_A, PWM_B, PWM_X) of a single submodule. Each output can independently select which faults affect it and how it responds during a fault.

Configuration per output:

- Disable Mask: Selects which fault inputs can disable this output
  - disableMask_ch0: Bits [0-3] for FAULT0-3
  - disableMask_ch1: Bits [0-3] for FAULT4-7 (dual-channel platforms only)
- Output Behavior: Specifies pin state during fault (Force 0, Force 1, or High-Z)

Note: Configuration applies to SMxDISMAP and SMxOCTRL registers. These registers are not affected by LDOK or FORCE_OUT; configuration takes effect immediately upon register write.

Note: For dual-channel platforms, specify disableMask_ch0 and disableMask_ch1 to control which faults (from either channel) can disable each output.

Note: For single-channel platforms, only disableMask_ch0 is used; disableMask_ch1 is conditionally compiled out.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- config – Pointer to the fault submodule configuration structure.

void FLEXPWM_ConfigFaultFilter(PWM_Type *base, uint8_t faultChannel, const *flexpwm_fault_filter_config_t* *config)

Configure fault filter for a FlexPWM fault channel.

This function configures the input filter for fault protection pins, including sampling period, sample count requirement, and glitch stretching logic.

The filter helps reject electrical noise and false fault triggers by requiring the FAULTx signal to be stable for N consecutive samples before a fault is reported. With GSTR enabled, narrow fault glitches (< 2 IPBus cycles) are automatically stretched.

Note: Prerequisites:

- Call *FLEXPWM_Init()* before this function to enable the peripheral clock.

Note: Configuration applies to the entire fault channel (FFILT register). For platforms with dual fault channels, call this function separately for each channel.

Note: Filter delay calculation:

- Without GSTR: delay = FILT_PER * (FILT_CNT + 3) IPBus cycles
- With GSTR: may be reduced due to glitch stretching logic

Note: To disable filtering:

- Set filterPeriod = 0 (sampling disabled, filter bypassed)

Parameters

- base – FlexPWM peripheral base address.
- faultChannel – Fault channel number (0 or 1 for dual-channel platforms).
- config – Pointer to the fault filter configuration structure.

void FLEXPWM_GetDefaultOutputTriggerConfig(*flexpwm_output_trigger_config_t* *config)

Get default configuration for output trigger.

This function initializes the output trigger configuration structure with safe default values:

- outTriggerEnable: 0 (all triggers disabled)
- triggerFrequency: kFLEXPWM_TriggerFrequency_EveryCycle (trigger every PWM cycle)
- muxTrig0Source: kFLEXPWM_TriggerMuxSource_GeneratedTrigger (use PWM_OUT_TRIG0)
- muxTrig1Source: kFLEXPWM_TriggerMuxSource_GeneratedTrigger (use PWM_OUT_TRIG1)
- stretchPrescaler: kFLEXPWM_StretchPrescaler_None (no prescaling, if supported)

After calling this function, the user should modify the fields as needed before calling *FLEXPWM_ConfigOutputTrigger()*.

void FLEXPWM_ConfigOutputTrigger(PWM_Type *base, uint8_t submodule, const *flexpwm_output_trigger_config_t* *config)

Configure output trigger for a FlexPWM submodule.

This function configures the output trigger parameters for a FlexPWM submodule, including:

- Trigger source mapping from VAL0-5 register matches (SMxTCTRL[OUT_TRIG_EN])
- Trigger output frequency control (SMxTCTRL[TRGFRQ])
- PWM_MUX_TRIG0 port source selection (SMxTCTRL[PWAOT0])
- PWM_MUX_TRIG1 port source selection (SMxTCTRL[PWBOT1])

The output trigger mechanism allows PWM events (counter matches with VAL registers) to trigger external modules such as ADC, DMA, or other peripherals for synchronized operation.

Note: Trigger source mapping:

- VAL0, VAL2, VAL4 matches generate PWM_OUT_TRIG0
- VAL1, VAL3, VAL5 matches generate PWM_OUT_TRIG1 Multiple sources can be enabled simultaneously (OR logic).

Note: Trigger frequency control (TRGFRQ): This setting only takes effect when CTRL[LDFQ] is non-zero (reload frequency divider active).

- false: Trigger outputs every PWM cycle regardless of reload occurrence
- true: Trigger outputs only on the last PWM cycle before a reload opportunity

---

Note: Port routing: PWM_MUX_TRIG0/1 ports can be routed to either:

- Generated trigger signals (PWM_OUT_TRIG0/1) from VAL register matches
- Direct PWM outputs (PWM_A/PWM_B) for waveform monitoring Both ports are independently configurable.

Note: Configuration takes effect immediately upon register write. This function does NOT require setting MCTRL[LDOK].

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- config – Pointer to the output trigger configuration structure.

void FLEXPWM_GetDefaultInputCaptureConfig(*flexpwm_input_capture_config_t* *config)

Get default configuration for input capture.

This function initializes the input capture configuration structure with safe default values. The default values are:

- All channels (A/B/X):
  - edge0 = kFLEXPWM_CaptureEdge_Disabled
  - edge1 = kFLEXPWM_CaptureEdge_Disabled
  - oneshot = false (free running mode)
  - inputSelect = kFLEXPWM_CaptureInput_RawSignal
  - edgeCompareValue = 0
  - fifoWatermark = kFLEXPWM_CaptureFifoWatermark_1

After calling this function, the user should modify the fields as needed before calling *FLEXPWM_ConfigInputCapture()*.

Parameters

- config – Pointer to the input capture configuration structure.

void FLEXPWM_GetDefaultCaptureFilterConfig(*flexpwm_capture_filter_config_t* *config)

Get default configuration for capture filter.

This function initializes the capture filter configuration structure with safe default values. The default values are:

- All channels (A/B/X):
  - filterPeriod = 0 (filter bypassed, sampling disabled)
  - filterCount = 0 (requires 3 consecutive samples)

After calling this function, the user should modify the fields as needed before calling *FLEXPWM_ConfigInputCaptureFilter()*.

Parameters

- config – Pointer to the capture filter configuration structure.

void FLEXPWM_ConfigInputCapture(PWM_Type *base, uint8_t submodule, const *flexpwm_input_capture_config_t* *config)

Configure input capture for a FlexPWM submodule.

This function configures the input capture parameters for up to three capture channels (Capture_A, Capture_B, Capture_X) of a FlexPWM submodule, including:

- Edge detection configuration for two edge detectors per channel (SMxCAPTCTRLA/B/X[EDGx0/1])
- One-shot or free-running mode (SMxCAPTCTRLA/B/X[ONESHOTx])

- Input source selection: raw signal or edge counter output (SMxCAPTCTRLA/B/X[INP_SELx])
- Edge counter compare value (SMxCAPTCOMPA/B/X[EDGCMPx])
- FIFO watermark level (SMxCAPTCTRLA/B/X[CFxWM])

Note: Edge counter behavior:

- When inputSelect = kFLEXPWM_CaptureInput_EdgeCounter, the edge counter is automatically enabled (EDGCNTx_EN = 1) by this function.
- When inputSelect = kFLEXPWM_CaptureInput_RawSignal, the edge counter remains disabled.

Note: Capture enable control:

- This function does NOT control the capture enable bits (ARMA/ARMB/ARMX).
- After calling this function, use a separate enable API to start capture operation.

Note: CVAL register mapping (NON-INTUITIVE):

- Capture_X: Edge0 -> CVAL0, Edge1 -> CVAL1
- Capture_A: Edge0 -> CVAL2, Edge1 -> CVAL3
- Capture_B: Edge0 -> CVAL4, Edge1 -> CVAL5

Note: Prerequisites:

- Call *FLEXPWM_Init()* before this function to enable the peripheral clock.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- config – Pointer to the input capture configuration structure.

void FLEXPWM_ConfigInputCaptureFilter(PWM_Type *base, uint8_t submodule, const *flexpwm_capture_filter_config_t* *config)

Configure input capture filter for a FlexPWM submodule.

This function configures the digital filter parameters for the three capture channels (Capture_A, Capture_B, Capture_X) of a FlexPWM submodule. The filter settings include:

- Filter sampling period (SMxCAPTFILTA/B/X[CAPTx_FILT_PER])
- Number of consecutive samples required (SMxCAPTFILTA/B/X[CAPTx_FILT_CNT])

The digital filter can eliminate glitches and noise on the capture input signals.

Note: Filter bypassing:

- Set filterPeriod = 0 to bypass the filter (no sampling, filter disabled).

Note: Filter delay calculation:

- Delay = filterPeriod * (filterCount + 3) IPBus clock cycles
- Example: filterPeriod=5, filterCount=2 -> delay = 5*(2+3) = 25 cycles

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Note: Hardware behavior:

- This function always writes 0 to the filter register first, then writes the configuration value. This ensures correct behavior per hardware requirements.

Note: Prerequisites:

- Call *FLEXPWM_Init()* before this function to enable the peripheral clock.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- config – Pointer to the capture filter configuration structure.

uint16_t FLEXPWM_GetInputCaptureValue(PWM_Type *base, uint8_t submodule, *flexpwm_capture_index_t* captureIndex)

Read captured value from a FlexPWM capture channel.

This function reads the captured counter value from one of the six capture value registers (CVAL0-5) for the specified capture channel and edge detector.

Note: CVAL register mapping (NON-INTUITIVE):

- kFLEXPWM_Capture_X_Edge0 -> CVAL0
- kFLEXPWM_Capture_X_Edge1 -> CVAL1
- kFLEXPWM_Capture_A_Edge0 -> CVAL2
- kFLEXPWM_Capture_A_Edge1 -> CVAL3
- kFLEXPWM_Capture_B_Edge0 -> CVAL4
- kFLEXPWM_Capture_B_Edge1 -> CVAL5

Warning: Destructive read:

- Reading a CVAL register decrements the FIFO count by 1.
- If the FIFO is empty, the read value is undefined.
- Check the FIFO empty flag (CFx) before reading to avoid invalid data.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- captureIndex – Capture channel and edge detector index (use flexpwm_capture_index_t enum).

Returns

The captured counter value (16-bit).

uint16_t FLEXPWM_GetInputCaptureCycle(PWM_Type *base, uint8_t submodule, *flexpwm_capture_index_t* captureIndex)

Read captured cycle counter value from a FlexPWM capture channel.

This function reads the captured cycle counter value from one of the six capture cycle registers (CCYC0-5) for the specified capture channel and edge detector. The cycle counter value represents the upper part of the extended timestamp when a capture event occurs.

Note: CCYC register mapping (matches CVAL mapping):

- kFLEXPWM_Capture_X_Edge0 -> CCYC0
- kFLEXPWM_Capture_X_Edge1 -> CCYC1
- kFLEXPWM_Capture_A_Edge0 -> CCYC2
- kFLEXPWM_Capture_A_Edge1 -> CCYC3
- kFLEXPWM_Capture_B_Edge0 -> CCYC4
- kFLEXPWM_Capture_B_Edge1 -> CCYC5

Note: Combined timestamp:

- The full timestamp is {CCYC, CVAL} (cycle counter as upper 16 bits, capture value as lower 16 bits), forming a 32-bit extended timestamp.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- captureIndex – Capture channel and edge detector index (use flexpwm_capture_index_t enum).

Returns

The captured cycle counter value (16-bit).

void FLEXPWM_EnableInputCapture(PWM_Type *base, uint8_t submodule, *flexpwm_capture_channel_t* channel)

Enable input capture for a FlexPWM capture channel.

This function enables input capture operation for the specified capture channel by setting the corresponding ARM bit (ARMA/ARMB/ARMX) in the capture control register.

Note: ARM bit behavior in one-shot mode: When the capture channel is configured for one-shot mode (ONESHOT = 1), the ARM bit automatically clears after two capture events complete.

Note: Prerequisites: Before enabling capture, ensure:

a. Capture channel is configured (FLEXPWM_ConfigInputCapture)

b. Edge detectors are configured (EDGA0/EDGA1, EDGB0/EDGB1, or EDGX0/EDGX1)

c. Counter is running (FLEXPWM_EnableSubmoduleCounter)

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- channel – Capture channel selection (use flexpwm_capture_channel_t enum).

void FLEXPWM_DisableInputCapture(PWM_Type *base, uint8_t submodule, *flexpwm_capture_channel_t* channel)

Disable input capture for a FlexPWM capture channel.

This function disables input capture operation for the specified capture channel by clearing the corresponding ARM bit (ARMA/ARMB/ARMX) in the capture control register.

Note: FIFO handling: Disabling capture does not flush the FIFO. Any previously captured values remain readable. Clear the capture flags (CFx0/CFx1) separately if needed.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- channel – Capture channel selection (use flexpwm_capture_channel_t enum).

static inline void FLEXPWM_SetINIT(PWM_Type *base, uint8_t submodule, uint16_t value)

Set the INIT register value for a FlexPWM submodule.

This function directly writes a value to the INIT register (initial count register). The INIT register defines the starting value of the counter when it is initialized.

Note: This function is intended for use in runtime scenarios such as interrupt handlers to dynamically adjust PWM parameters. It performs a direct register write without checking or managing MCTRL[LDOK]. Users are responsible for:

- Ensuring LDOK is clear before calling this function
- Setting LDOK after updating registers to trigger reload
- Managing reload timing and synchronization

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- value – The value to write to the INIT register (16-bit).

static inline void FLEXPWM_SetVAL0(PWM_Type *base, uint8_t submodule, uint16_t value)

Set the VAL0 register value for a FlexPWM submodule.

This function directly writes a value to the VAL0 register. VAL0 defines the half-cycle reload point for the PWM counter.

Note: This function is intended for use in runtime scenarios such as interrupt handlers to dynamically adjust PWM parameters. It performs a direct register write without checking or managing MCTRL[LDOK]. Users are responsible for reload timing.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- value – The value to write to the VAL0 register (16-bit).

static inline void FLEXPWM_SetVAL1(PWM_Type *base, uint8_t submodule, uint16_t value)

Set the VAL1 register value for a FlexPWM submodule.

This function directly writes a value to the VAL1 register. VAL1 defines the modulo (period) value for the PWM counter.

Note: This function is intended for use in runtime scenarios such as interrupt handlers to dynamically adjust PWM period. It performs a direct register write without checking or managing MCTRL[LDOK]. Users are responsible for reload timing.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- value – The value to write to the VAL1 register (16-bit).

static inline void FLEXPWM_SetVAL2(PWM_Type *base, uint8_t submodule, uint16_t value)

Set the VAL2 register value for a FlexPWM submodule.

This function directly writes a value to the VAL2 register. VAL2 defines the count value at which PWM23 (PWM_A) is set high, controlling the turn-on edge of PWM_A output.

Note: This function is intended for use in runtime scenarios such as interrupt handlers to dynamically adjust PWM_A duty cycle. It performs a direct register write without checking or managing MCTRL[LDOK]. Users are responsible for reload timing.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- value – The value to write to the VAL2 register (16-bit).

static inline void FLEXPWM_SetVAL3(PWM_Type *base, uint8_t submodule, uint16_t value)

Set the VAL3 register value for a FlexPWM submodule.

This function directly writes a value to the VAL3 register. VAL3 defines the count value at which PWM23 (PWM_A) is set low, controlling the turn-off edge of PWM_A output.

Note: This function is intended for use in runtime scenarios such as interrupt handlers to dynamically adjust PWM_A duty cycle. It performs a direct register write without checking or managing MCTRL[LDOK]. Users are responsible for reload timing.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).

- value – The value to write to the VAL3 register (16-bit).

static inline void FLEXPWM_SetVAL4(PWM_Type *base, uint8_t submodule, uint16_t value)

Set the VAL4 register value for a FlexPWM submodule.

This function directly writes a value to the VAL4 register. VAL4 defines the count value at which PWM45 (PWM_B) is set high, controlling the turn-on edge of PWM_B output.

Note: This function is intended for use in runtime scenarios such as interrupt handlers to dynamically adjust PWM_B duty cycle. It performs a direct register write without checking or managing MCTRL[LDOK]. Users are responsible for reload timing.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- value – The value to write to the VAL4 register (16-bit).

static inline void FLEXPWM_SetVAL5(PWM_Type *base, uint8_t submodule, uint16_t value)

Set the VAL5 register value for a FlexPWM submodule.

This function directly writes a value to the VAL5 register. VAL5 defines the count value at which PWM45 (PWM_B) is set low, controlling the turn-off edge of PWM_B output.

Note: This function is intended for use in runtime scenarios such as interrupt handlers to dynamically adjust PWM_B duty cycle. It performs a direct register write without checking or managing MCTRL[LDOK]. Users are responsible for reload timing.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- value – The value to write to the VAL5 register (16-bit).

static inline void FLEXPWM_SetDTCNT0(PWM_Type *base, uint8_t submodule, uint16_t value)

Set the DTCNT0 register value for a FlexPWM submodule.

This function directly writes a value to the DTCNT0 register (deadtime count register 0). DTCNT0 specifies the number of IPBus clock cycles for deadtime delay insertion, independent of the PWM clock prescaler settings (CTRL[PRSC] and CTRL2[CLK_SEL]). DTCNT0 inserts software-selectable activation delays at PWM_A turn-on edge.

Note: DTCNT0 is an 11-bit register with valid range 0-0x7FF. Values exceeding this range will be masked to 11 bits.

Note: This function applies only to complementary PWM mode.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).

- value – The value to write to the DTCNT0 register (11-bit, range: 0-0x7FF).

static inline void FLEXPWM_SetDTCNT1(PWM_Type *base, uint8_t submodule, uint16_t value)

Set the DTCNT1 register value for a FlexPWM submodule.

This function directly writes a value to the DTCNT1 register (deadtime count register 1). DTCNT1 specifies the number of IPBus clock cycles for deadtime delay insertion, independent of the PWM clock prescaler settings (CTRL[PRSC] and CTRL2[CLK_SEL]). DTCNT1 inserts software-selectable activation delays at PWM_B turn-on edge.

Note: DTCNT1 is an 11-bit register with valid range 0-0x7FF. Values exceeding this range will be masked to 11 bits.

Note: This function applies only to complementary PWM mode.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- value – The value to write to the DTCNT1 register (11-bit, range: 0-0x7FF).

static inline void FLEXPWM_SetPhaseDelay(PWM_Type *base, uint8_t submodule, uint16_t value)

Set the Phase Delay register value for a FlexPWM submodule.

This function directly writes a value to the PHASEDLY register (phase delay register). PHASEDLY defines the time delay from the master sync signal (from submodule 0) to when this submodule recognizes the master sync, specified in PWM clock cycles.

Setting this register to a non-zero value and using the master sync signal as the initialization source allows this submodule's output to be delayed by a fixed number of cycles relative to submodule 0, enabling phase-shifted PWM outputs.

Note: PHASEDLY is only valid for submodules 1-3. Submodule 0 is the master sync source and cannot have a phase delay relative to itself.

Note: This function is intended for use in runtime scenarios such as interrupt handlers to dynamically adjust phase delay. It performs a direct register write without checking or managing MCTRL[LDOK]. Users are responsible for reload timing.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (1-3, must NOT be 0).
- value – The value to write to the PHASEDLY register (16-bit).

static inline void FLEXPWM_SetCompareMode(PWM_Type *base, uint8_t submodule, *flexpwm_compare_mode_t* compareMode)

Set Compare Mode for a FlexPWM submodule.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- compareMode – The compare mode to set for the submodule.

static inline void FLEXPWM_MaskPWMOutput(PWM_Type *base, uint16_t aMask, uint16_t bMask, uint16_t xMask)

Mask PWM_A, PWM_B, PWM_X outputs for specified submodules.

This function sets the MASK register bits to mask (disable) PWM outputs by forcing them to logic 0 before output polarity is applied. The mask takes effect when a FORCE_OUT event occurs on the corresponding submodule, unless immediate update is enabled.

Note: MASK register characteristics:

- Double-buffered register: writes take effect on next FORCE_OUT event
- Use *FLEXPWM_EnableUpdateMaskImmediately()* to bypass FORCE_OUT requirement
- Masking forces output to logic 0 before polarity inversion

Note: This function performs read-modify-write to preserve:

- Mask settings for other submodules not specified in parameters
- UPDATE_MASK bits (on platforms with FSL_FEATURE_PWM_MASK_HAS_UPDATE_MASK_BITFIELD)

Parameters

- base – FlexPWM peripheral base address.
- aMask – Submodule mask for PWM_A outputs (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.
- bMask – Submodule mask for PWM_B outputs (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.
- xMask – Submodule mask for PWM_X outputs (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.

static inline void FLEXPWM_UnMaskPWMOutput(PWM_Type *base, uint16_t aMask, uint16_t bMask, uint16_t xMask)

Unmask PWM_A, PWM_B, PWM_X outputs for specified submodules.

This function clears the MASK register bits to unmask (enable) PWM outputs. The unmask takes effect when a FORCE_OUT event occurs on the corresponding submodule, unless immediate update is enabled.

Parameters

- base – FlexPWM peripheral base address.
- aMask – Submodule mask for PWM_A outputs (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.
- bMask – Submodule mask for PWM_B outputs (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.

- xMask – Submodule mask for PWM_X outputs (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.

static inline void FLEXPWM_EnableUpdateMaskImmediately(PWM_Type *base, uint16_t submoduleMask)

Enable immediate MASK register update for specified submodules.

This function configures the specified submodules to update their MASK register values immediately, bypassing the FORCE_OUT event requirement. This is useful for emergency stop or fault protection scenarios where immediate output masking is required.

Note: MASK[UPDATE_MASK] register characteristics:

- Setting a bit to 1 enables immediate MASK update for that submodule
- Once enabled, MASK updates take effect immediately without waiting for FORCE_OUT

Parameters

- base – FlexPWM peripheral base address.
- submoduleMask – Submodule selection mask (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.

static inline void FLEXPWM_SetPWMSource23(PWM_Type *base, uint8_t submodule, uint16_t source)

Set PWM source for PWM23 (PWM_A) of a submodule.

This function selects the signal source that feeds into the deadtime insertion logic for PWM23 (PWM_A) output by configuring the DTSRCSEL register. The setting takes effect when a FORCE_OUT event occurs on the submodule.

Available sources:

- Generated PWM: Normal PWM signal from PWM generator
- Inverted PWM: Inverted version of generated PWM
- Software: Software-controlled value from SWCOUT register
- External: External input signal

Note: DTSRCSEL register characteristics:

- Double-buffered: Changes take effect on next FORCE_OUT event
- NOT affected by MCTRL[LDOK]: Independent of reload mechanism
- Global register: This function performs read-modify-write to protect other submodules

---

Note: When source is set to kFLEXPWM_ForcePwmSource_Software, use *FLEXPWM_SetSoftwareControlOutput23()* to set the output value.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).

- source – PWM source selection (use flexpwm_force_pwm_source_t enum).

static inline void FLEXPWM_SetPWMSource45(PWM_Type *base, uint8_t submodule, uint16_t source)

Set PWM source for PWM45 (PWM_B) of a submodule.

This function selects the signal source that feeds into the deadtime insertion logic for PWM45 (PWM_B) output by configuring the DTSRCSEL register. The setting takes effect when a FORCE_OUT event occurs on the submodule.

Note: See *FLEXPWM_SetPWMSource23()* documentation for detailed information about source selection, register characteristics, and usage notes.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- source – PWM source selection (use flexpwm_force_pwm_source_t enum).

static inline void FLEXPWM_SetSoftwareControlOutput23(PWM_Type *base, uint8_t submodule, uint16_t softwareValue)

Set software-controlled output value for PWM23 (PWM_A) of a submodule.

This function sets the software-controlled PWM output value in the SWCOUT register. This value is used as the PWM source when DTSRCSEL is configured to select software control (kFLEXPWM_ForcePwmSource_Software). The setting takes effect when a FORCE_OUT event occurs on the submodule.

Note: SWCOUT register characteristics:

- Double-buffered: Changes take effect on next FORCE_OUT event
- NOT affected by MCTRL[LDOK]: Independent of reload mechanism
- Global register: This function performs read-modify-write to protect other submodules

---

Note: Typical usage sequence:

a. Call FLEXPWM_SetPWMSource23(base, kFLEXPWM_ForcePwmSource_Software, submodule)

b. Call FLEXPWM_SetSoftwareControlOutput23(base, value, submodule)

c. Trigger FORCE_OUT event to make both settings take effect

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- softwareValue – Software control output value (0 or 1).
  - 0: Logic 0 provided to deadtime logic instead of PWM23
  - 1: Logic 1 provided to deadtime logic instead of PWM23

static inline void FLEXPWM_SetSoftwareControlOutput45(PWM_Type *base, uint8_t submodule, uint16_t softwareValue)

Set software-controlled output value for PWM45 (PWM_B) of a submodule.

This function sets the software-controlled PWM output value in the SWCOUT register. This value is used as the PWM source when DTSRCSEL is configured to select software control (kFLEXPWM_ForcePwmSource_Software).

Note: See *FLEXPWM_SetSoftwareControlOutput23()* documentation for detailed information about register characteristics, usage sequence, and notes.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- softwareValue – Software control output value (0 or 1).
  - 0: Logic 0 provided to deadtime logic instead of PWM45
  - 1: Logic 1 provided to deadtime logic instead of PWM45

static inline void FLEXPWM_SetComplementaryPWMSource23(PWM_Type *base, uint16_t submoduleMask)

Select PWM23 (PWM_A) as complementary PWM source for specified submodules.

This function configures the MCTRL[IPOL] register to select PWM23 (PWM_A) as the source for generating complementary PWM pair outputs in complementary mode. The setting takes effect when a FORCE_OUT event occurs on the submodule.

In complementary mode:

- PWM_A output: PWM23 signal (non-inverted)
- PWM_B output: ~PWM23 signal (inverted complement)

Note: MCTRL[IPOL] register characteristics:

- Takes effect on FORCE_OUT event (double-buffered behavior)
- Only applies when submodule is in complementary mode (INDEP = 0)
- Ignored in independent mode (INDEP = 1)

Note: This function clears IPOL bits for specified submodules (IPOL = 0 selects PWM23).

Parameters

- base – FlexPWM peripheral base address.
- submoduleMask – Submodule selection mask (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.

static inline void FLEXPWM_SetComplementaryPWMSource45(PWM_Type *base, uint16_t submoduleMask)

Select PWM45 (PWM_B) as complementary PWM source for specified submodules.

This function configures the MCTRL[IPOL] register to select PWM45 (PWM_B) as the source for generating complementary PWM pair outputs in complementary mode. The setting takes effect when a FORCE_OUT event occurs on the submodule.

In complementary mode:

- PWM_A output: ~PWM45 signal (inverted complement)
- PWM_B output: PWM45 signal (non-inverted)

Note: See *FLEXPWM_SetComplementaryPWMSource23()* documentation for detailed information about MCTRL[IPOL] characteristics and complementary mode operation.

Note: This function sets IPOL bits for specified submodules (IPOL = 1 selects PWM45).

Parameters

- base – FlexPWM peripheral base address.
- submoduleMask – Submodule selection mask (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.

static inline void FLEXPWM_SetLoadOkay(PWM_Type *base, uint16_t submoduleMask)

Set Load Okay (LDOK) for specified submodules.

This function sets the MCTRL[LDOK] bits to enable register reload for the specified submodules. When LDOK is set, buffered register values will be transferred to active registers according to the reload mode and timing configured in CTRL[LDMOD, LDFQ, HALF, FULL].

Note: LDOK behavior:

- Can only be set when the corresponding LDOK bit is currently 0
- Automatically cleared by hardware after reload completes
- Can be manually cleared using *FLEXPWM_ClearLoadOkay()*
- While LDOK=1, writes to buffered registers are blocked

Note: Typical usage flow:

a. Modify buffered registers (VAL0-5, INIT, etc.) using FLEXPWM_SetVALx() or similar
b. Call *FLEXPWM_SetLoadOkay()* to trigger reload
c. Hardware transfers buffered values at the configured reload opportunity
d. LDOK automatically clears after reload completes

Parameters

- base – FlexPWM peripheral base address.
- submoduleMask – Submodule selection mask (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.

static inline void FLEXPWM_ClearLoadOkay(PWM_Type *base, uint16_t submoduleMask)

Clear Load Okay (LDOK) for specified submodules.

This function clears the MCTRL[LDOK] bits by writing to MCTRL[CLDOK] bits. This cancels a pending reload operation for the specified submodules.

Note: MCTRL[CLDOK] (Clear LDOK) mechanism:

- Writing 1 to CLDOK[x] clears the corresponding LDOK[x] bit
- CLDOK is write-only; reading always returns 0
- Use this when you need to cancel a pending reload

Parameters

- base – FlexPWM peripheral base address.
- submoduleMask – Submodule selection mask (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.

static inline uint16_t FLEXPWM_GetLoadOkay(PWM_Type *base)

Get Load Okay (LDOK) status.

This function reads the MCTRL[LDOK] bits to check which submodules have pending reload operations.

Note: Return value format:

- Bit[0]: Submodule 0 LDOK status
- Bit[1]: Submodule 1 LDOK status
- Bit[2]: Submodule 2 LDOK status
- Bit[3]: Submodule 3 LDOK status

Note: Usage example:

```
uint16_t ldokStatus = FLEXPWM_GetLoadOkay(PWM0);
if (ldokStatus & kFLEXPWM_SubmoduleMask_0) {
}
```

Parameters

- base – FlexPWM peripheral base address.

Returns

LDOK status bits (bit[3:0] correspond to submodules 3-0). Use flexpwm_submodule_mask_t enum values to check specific submodules.

static inline void FLEXPWM_SetLocalForceOut(PWM_Type *base, uint8_t submodule)

Set local FORCE_OUT event for a submodule.

This function sets the SMxCTRL2[FORCE] bit to trigger a local FORCE_OUT event. When a FORCE_OUT event occurs, several double-buffered registers immediately update:

- DTSRCSEL (PWM source selection)
- SWCOUT (software-controlled output values)

- MASK (output masking)
- MCTRL[IPOL] (complementary PWM source selection)

Additionally, if CTRL2[FRCEN] is enabled and the counter is running, the counter will be initialized to the INIT register value.

Note: FORCE_OUT trigger source: This function triggers a local FORCE_OUT event by setting CTRL2[FORCE]. The FORCE_OUT event only occurs if CTRL2[FORCE_SEL] = 0 (local force selected). If FORCE_SEL selects a different source, setting FORCE has no effect.

Note: Counter initialization: The counter is reinitialized only if:

- CTRL2[FRCEN] = 1 (force initialization enabled), AND
- MCTRL[RUN] = 1 (counter running) OR CTRL2[CLK_SEL] = 2 (submodule 0 aux clock)

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).

static inline void FLEXPWM_SetCounterForceInitialization(PWM_Type *base, uint8_t submodule, bool enable)

Enable or disable counter initialization on FORCE_OUT event.

This function controls whether FORCE_OUT events can trigger counter initialization by configuring the CTRL2[FRCEN] bit. When enabled, the counter will be reset to the INIT register value when local software forced event occurs.

Note: Counter initialization conditions: The counter is reinitialized only when ALL of the following conditions are met:

- CTRL2[FRCEN] = 1 (enabled via this function), AND
- A local FORCE_OUT event occurs (CTRL2[FORCE_SEL] = 0, CTRL2[FORCE] = 1)

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- enable – Enable or disable counter force initialization:
  - true: FORCE_OUT events can trigger counter initialization (FRCEN = 1)
  - false: FORCE_OUT events do not affect counter initialization (FRCEN = 0)

static inline void FLEXPWM_EnableSubmoduleCounter(PWM_Type *base, uint16_t submoduleMask)

Enable PWM counter for specified submodules.

This function enables the PWM counters for the specified submodules by setting MCTRL[RUN] bits. When enabled, the counters start running and generating PWM waveforms.

Note: Effects of enabling counter (RUN=1):

- Counter begins incrementing/decrementing according to configuration
- PWM generation starts (if outputs are also enabled)
- Reload events can occur at configured opportunities
- FORCE_OUT can trigger counter initialization (if FRCEN enabled)

Parameters

- base – FlexPWM peripheral base address.
- submoduleMask – Submodule selection mask (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.

static inline void FLEXPWM_DisableSubmoduleCounter(PWM_Type *base, uint16_t submoduleMask)

Disable PWM counter for specified submodules.

This function disables the PWM counters for the specified submodules by clearing MCTRL[RUN] bits. When disabled, the counters stop running but retain their configuration.

Note: Effects of disabling counter (RUN=0):

- Counter stops incrementing/decrementing
- PWM generation ceases (outputs hold last state or go to fault state)
- Configuration registers remain intact
- Fault clearing behavior changes (see fault protection documentation)

Parameters

- base – FlexPWM peripheral base address.
- submoduleMask – Submodule selection mask (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.

static inline void FLEXPWM_EnablePWMOutput(PWM_Type *base, uint16_t aMask, uint16_t bMask, uint16_t xMask)

Enable PWM_A, PWM_B, PWM_X outputs for specified submodules.

This function enables PWM outputs by setting the corresponding bits in the OUTEN register. Each output (PWM_A, PWM_B, PWM_X) can be independently enabled for each submodule.

Note: OUTEN register layout (same as MASK register):

- bit[11:8]: PWMA_EN - PWM_A output enable for submodules 3-0
- bit[7:4]: PWMB_EN - PWM_B output enable for submodules 3-0
- bit[3:0]: PWMX_EN - PWM_X output enable for submodules 3-0

Note: Prerequisites: Before enabling outputs, ensure:

a. PWM waveform is configured (FLEXPWM_ConfigPWM)

b. Counter is running (FLEXPWM_EnableSubmoduleCounter)

c. Outputs are not masked (check MASK register)

Parameters

- base – FlexPWM peripheral base address.
- aMask – Submodule mask for PWM_A outputs (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.
- bMask – Submodule mask for PWM_B outputs (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.
- xMask – Submodule mask for PWM_X outputs (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.

static inline void FLEXPWM_DisablePWMOutput(PWM_Type *base, uint16_t aMask, uint16_t bMask, uint16_t xMask)

Disable PWM_A, PWM_B, PWM_X outputs for specified submodules.

This function disables PWM outputs by clearing the corresponding bits in the OUTEN register. When an output is disabled, the pin is released from FlexPWM control and may be controlled by other peripherals or GPIO.

Note: Output disable effects:

- Pin is tri-stated or controlled by GPIO/other peripherals
- PWM waveform generation continues internally
- Re-enabling the output will resume PWM operation seamlessly

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Parameters

- base – FlexPWM peripheral base address.
- aMask – Submodule mask for PWM_A outputs (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.
- bMask – Submodule mask for PWM_B outputs (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.
- xMask – Submodule mask for PWM_X outputs (OR'ed combination of flexpwm_submodule_mask_t). bit[0]=SM0, bit[1]=SM1, bit[2]=SM2, bit[3]=SM3.

static inline void FLEXPWM_SetWriteProtection(PWM_Type *base, *flexpwm_write_protect_t* config)

Set FlexPWM write protection mode.

This function configures the write protection for FlexPWM registers by setting MCTRL2[WRPROT]. Write protection prevents accidental modification of critical PWM configuration registers.

Note: Write protection modes:

- kFLEXPWM_WriteProtect_Off: Write protection is disabled (default after reset)

- kFLEXPWM_WriteProtect_On: Write protection is enabled but can be disabled
- kFLEXPWM_WriteProtect_OffLocked: Write protection is disabled and locked until chip reset
- kFLEXPWM_WriteProtect_OnLocked: Write protection is enabled and locked until chip reset

Note: Once a locked mode is set (OffLocked or OnLocked), the write protection state cannot be changed until the next chip reset. Use locked modes for safety-critical applications.

Parameters

- base – FlexPWM peripheral base address.
- config – Write protection mode selection.

static inline void FLEXPWM_EnableSubmoduleInterrupts(PWM_Type *base, uint8_t submodule, uint16_t mask)

Enable FlexPWM submodule interrupts.

This function enables the specified interrupt sources for a FlexPWM submodule by setting the corresponding bits in the SMxINTEN register.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- mask – Interrupt enable mask (OR'ed combination of _flexpwm_submodule_interrupt_enable flags).

static inline void FLEXPWM_DisableSubmoduleInterrupts(PWM_Type *base, uint8_t submodule, uint16_t mask)

Disable FlexPWM submodule interrupts.

This function disables the specified interrupt sources for a FlexPWM submodule by clearing the corresponding bits in the SMxINTEN register.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- mask – Interrupt disable mask (OR'ed combination of _flexpwm_submodule_interrupt_enable flags).

static inline uint16_t FLEXPWM_GetSubmoduleStatusFlags(PWM_Type *base, uint8_t submodule)

Get FlexPWM submodule status flags.

This function returns the current status flags from the SMxSTS register.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).

Returns

Current status flags (combination of _flexpwm_submodule_status_flag values).

static inline void FLEXPWM_ClearSubmoduleStatusFlags(PWM_Type *base, uint8_t submodule, uint16_t mask)

Clear FlexPWM submodule status flags.

This function clears the specified status flags in the SMxSTS register using the write-1-to-clear (W1C) mechanism.

Note: Do not attempt to clear kFLEXPWM_RegisterUpdatedFlag (RUF) as it is read-only.

Parameters

- base – FlexPWM peripheral base address.
- submodule – Submodule number (0-3).
- mask – Status flag clear mask (OR'ed combination of _flexpwm_submodule_status_flag values). To clear a flag, set the corresponding bit to 1 in the mask.

static inline void FLEXPWM_EnableFaultInterrupts(PWM_Type *base, uint8_t faultChannel, uint16_t mask)

Enable FlexPWM fault interrupts.

This function enables the specified fault interrupt sources by setting the corresponding bits in the FCTRL[FIE] field.

Note: For dual-channel platforms (FSL_FEATURE_PWM_FAULT_CH_COUNT > 1): The same mask bit values are used for both fault channels. The faultChannel parameter determines which set of fault inputs is controlled:

- faultChannel = 0: Controls FAULT0-3 interrupts
- faultChannel = 1: Controls FAULT4-7 interrupts

Parameters

- base – FlexPWM peripheral base address.
- faultChannel – Fault channel number:
  - 0: Fault channel 0 (FAULT0-3)
  - 1: Fault channel 1 (FAULT4-7, if supported)
- mask – Fault interrupt enable mask (OR'ed combination of _flexpwm_fault_interrupt_enable flags).

static inline void FLEXPWM_DisableFaultInterrupts(PWM_Type *base, uint8_t faultChannel, uint16_t mask)

Disable FlexPWM fault interrupts.

This function disables the specified fault interrupt sources by clearing the corresponding bits in the FCTRL[FIE] field.

Parameters

- base – FlexPWM peripheral base address.
- faultChannel – Fault channel number:
  - 0: Fault channel 0 (FAULT0-3)
  - 1: Fault channel 1 (FAULT4-7, if supported)

- mask – Fault interrupt disable mask (OR'ed combination of _flexpwm_fault_interrupt_enable flags).

static inline uint16_t FLEXPWM_GetFaultStatusFlags(PWM_Type *base, uint8_t faultChannel)

Get FlexPWM fault status flags.

This function returns the current fault status flags (FFLAG bits) from the FSTS register. These are latched flags that indicate a fault event has occurred.

Note: To check real-time hardware pin status (rather than latched flags), use *FLEXPWM_GetFaultFilteredPinStatusFlags()* instead.

Parameters

- base – FlexPWM peripheral base address.
- faultChannel – Fault channel number:
  - 0: Fault channel 0 (FAULT0-3)
  - 1: Fault channel 1 (FAULT4-7, if supported)

Returns

Current fault flags (combination of _flexpwm_fault_status_flag values).

static inline void FLEXPWM_ClearFaultStatusFlags(PWM_Type *base, uint8_t faultChannel, uint16_t mask)

Clear FlexPWM fault status flags.

This function clears the specified fault status flags (FFLAG bits) in the FSTS register using the write-1-to-clear (W1C) mechanism.

Note: Clearing FFLAG does not automatically re-enable PWM outputs. The re-enable timing depends on fault clearing mode (FAUTO), safety mode (FSAFE), recovery timing (FHALF/FFULL), and the state of FFPIN (filtered pin status).

Parameters

- base – FlexPWM peripheral base address.
- faultChannel – Fault channel number:
  - 0: Fault channel 0 (FAULT0-3)
  - 1: Fault channel 1 (FAULT4-7, if supported)
- mask – Fault flag clear mask (OR'ed combination of _flexpwm_fault_status_flag values). To clear a flag, set the corresponding bit to 1 in the mask.

static inline uint16_t FLEXPWM_GetFaultFilteredPinStatusFlags(PWM_Type *base, uint8_t faultChannel)

Get FlexPWM filtered fault pin status.

This function returns the real-time status of fault pins after filtering (FFPIN bits) from the FSTS register. These are read-only hardware status bits that reflect the current state of external fault signals.

Note: Key differences:

- FFLAG: Software-clearable latched flag (historical event - "a fault occurred")

- FFPIN: Read-only real-time status (current state - “fault is active now”)

Parameters

- base – FlexPWM peripheral base address.
- faultChannel – Fault channel number:
  - 0: Fault channel 0 (FAULT0-3 pins)
  - 1: Fault channel 1 (FAULT4-7 pins, if supported)

Returns

Current filtered fault pin status (combination of _flexpwm_fault_pin_status values).

void FLEXPWM_ConfigDMA(PWM_Type *base, uint8_t submodule, const *flexpwm_dma_config_t* *config)

Configures the DMA control strategy for a FlexPWM submodule.

This function configures the DMA trigger source and FIFO watermark logic. These settings define the DMA request generation strategy and should typically be configured once during initialization.

Note: This function only configures CAPTDE[7:6] and FAND bits in SMxDMAEN register. To enable/disable individual DMA channels at runtime, use *FLEXPWM_EnableDMA()* and *FLEXPWM_DisableDMA()*.

Note: Prerequisites: Before calling this function, ensure:

a. FIFO watermark levels are configured in *FLEXPWM_ConfigInputCapture()*

b. Capture channels are properly configured if using capture DMA

Parameters

- base – FlexPWM peripheral base address
- submodule – FlexPWM submodule number (0-3)
- config – Pointer to DMA configuration structure

static inline void FLEXPWM_EnableDMA(PWM_Type *base, uint8_t submodule, uint16_t mask)

Enable FlexPWM submodule DMA requests.

This function enables DMA request generation for the specified channels. It controls the VALDE bit (VALx/FRACVALx write) and capture channel enables (CX0DE, CX1DE, CB0DE, CB1DE, CA0DE, CA1DE).

Note: Before calling this function, ensure *FLEXPWM_ConfigDMA()* has been called to set up the DMA trigger strategy.

Parameters

- base – FlexPWM peripheral base address
- submodule – FlexPWM submodule number (0-3)
- mask – Bit mask of DMA enable flags (OR’ed combination of _flexpwm_dma_enable)

static inline void FLEXPWM_DisableDMA(PWM_Type *base, uint8_t submodule, uint16_t mask)

Disable FlexPWM submodule DMA requests.

This function disables DMA request generation for the specified channels.

Parameters

- base – FlexPWM peripheral base address
- submodule – FlexPWM submodule number (0-3)
- mask – Bit mask of DMA enable flags (OR'ed combination of _flexpwm_dma_enable)

FSL_FLEXPWM_DRIVER_VERSION

Version 2.0.0

enum _flexpwm_clock_source

FlexPWM clock source selection.

Values:

enumerator kFLEXPWM_ClockSource_IPBusClock

IPBus clock

enumerator kFLEXPWM_ClockSource_ExtClock

External clock (EXT_CLK)

enumerator kFLEXPWM_ClockSource_Submodule0Clock

Submodule 0 auxiliary clock

enum _flexpwm_prescaler

FlexPWM clock prescaler selection.

Values:

enumerator kFLEXPWM_Prescale_Divide_1

Divide by 1

enumerator kFLEXPWM_Prescale_Divide_2

Divide by 2

enumerator kFLEXPWM_Prescale_Divide_4

Divide by 4

enumerator kFLEXPWM_Prescale_Divide_8

Divide by 8

enumerator kFLEXPWM_Prescale_Divide_16

Divide by 16

enumerator kFLEXPWM_Prescale_Divide_32

Divide by 32

enumerator kFLEXPWM_Prescale_Divide_64
Divide by 64

enumerator kFLEXPWM_Prescale_Divide_128
Divide by 128

enum _flexpwm_load_mode
FlexPWM load mode selection.
Values:

enumerator kFLEXPWM_LoadMode_Opportunity
Load at PWM reload opportunity

enumerator kFLEXPWM_LoadMode_Immediate
Load immediately after LDOK is set

enum _flexpwm_reload_source
FlexPWM reload source selection.
Values:

enumerator kFLEXPWM_ReloadSource_LocalReload
Local reload signal

enumerator kFLEXPWM_ReloadSource_MasterReload
Master reload signal from submodule 0

enum _flexpwm_init_source
FlexPWM counter initialization source selection.
Values:

enumerator kFLEXPWM_InitSource_LocalSync
Local sync signal

enumerator kFLEXPWM_InitSource_MasterReload
Master reload signal from submodule 0

enumerator kFLEXPWM_InitSource_MasterSync
Master sync signal from submodule 0

enumerator kFLEXPWM_InitSource_ExtSync
External sync signal (EXT_SYNC)

enum _flexpwm_compare_mode
FlexPWM PWM compare mode selection.
Values:

enumerator kFLEXPWM_CompareMode_Equal
Compare when counter equals compare value

enumerator kFLEXPWM_CompareMode_EqualGreater
Compare when counter is equal or greater than compare value

enum _flexpwm_submodule_mask
FlexPWM submodule mask for multi-submodule operations.

These flags can be OR'ed together to specify multiple submodules simultaneously. Used with functions that operate on multiple submodules at once.

Values:

enumerator kFLEXPWM_SubmoduleMask_0
Submodule 0

enumerator kFLEXPWM_SubmoduleMask_1
Submodule 1

enumerator kFLEXPWM_SubmoduleMask_2
Submodule 2

enum _flexpwm_pwm_polarity
FlexPWM PWM output polarity selection.

Values:

enumerator kFLEXPWM_Polarity_ActiveHigh
PWM signal is normal (active high)

enumerator kFLEXPWM_Polarity_ActiveLow
PWM signal is inverted (active low)

enum _flexpwm_ipol_source
FlexPWM PWM output source selection for complementary mode.

Values:

enumerator kFLEXPWM_IPOL_PWM23
Use PWM23 (PWM_A) as complementary PWM source

enumerator kFLEXPWM_IPOL_PWM45
Use PWM45 (PWM_B) as complementary PWM source

enum _flexpwm_force_output_source
FlexPWM FORCE_OUT event source selection.

Values:

enumerator kFLEXPWM_ForceOutputSource_LocalForce
Local software forced event

enumerator kFLEXPWM_ForceOutputSource_MasterForce
Master force signal from submodule 0

enumerator kFLEXPWM_ForceOutputSource_LocalReload
Local reload signal

enumerator kFLEXPWM_ForceOutputSource_MasterReload
Master reload signal from submodule 0

enumerator kFLEXPWM_ForceOutputSource_LocalSync
Local sync signal

enumerator kFLEXPWM_ForceOutputSource_MasterSync
Master sync signal from submodule 0

enumerator kFLEXPWM_ForceOutputSource_ExtForce
External force signal (EXT_FORCE)

enumerator kFLEXPWM_ForceOutputSource_ExtSync
External sync signal (EXT_SYNC)

enum _flexpwm_force_pwm_source
FlexPWM PWM source selection for deadtime logic (DTSRCSEL)
Values:

enumerator kFLEXPWM_ForcePwmSource_Generated
Generated PWM signal

enumerator kFLEXPWM_ForcePwmSource_Inverted
Inverted PWM signal

enumerator kFLEXPWM_ForcePwmSource_Software
Software controlled output (SWCOUT)

enumerator kFLEXPWM_ForcePwmSource_External
External signal

enum _flexpwm_fault_output_behavior
FlexPWM fault output behavior during fault condition.
Defines how PWM outputs respond when a fault is detected. Values map directly to SMxOCTRL[PWMAFS/PWMBFS/PWMXFS] bitfields.
Values:

enumerator kFLEXPWM_FaultOutput_Force0
0b00 - Force output to logic 0

enumerator kFLEXPWM_FaultOutput_Force1
0b01 - Force output to logic 1

enumerator kFLEXPWM_FaultOutput_HighZ
0b10/0b11 - High impedance (3-state) output

enum _flexpwm_fault_mask

FlexPWM fault input mask for fault protection configuration.

These flags can be OR'ed together to configure multiple fault inputs simultaneously with the same protection parameters. Used with *FLEXPWM_ConfigFaultProtection()* function.

Note: For dual-channel platforms (FSL_FEATURE_PWM_FAULT_CH_COUNT > 1):

- When faultChannel = 0: Use kFLEXPWM_FaultMask_0/1/2/3 for FAULT0-3
- When faultChannel = 1: Use kFLEXPWM_FaultMask_0/1/2/3 for FAULT4-7 The enum values are the same, but the channel parameter determines which physical fault inputs are configured.

Values:

enumerator kFLEXPWM_FaultMask_0

FAULT0 (ch0) or FAULT4 (ch1)

enumerator kFLEXPWM_FaultMask_1

FAULT1 (ch0) or FAULT5 (ch1)

enumerator kFLEXPWM_FaultMask_2

FAULT2 (ch0) or FAULT6 (ch1)

enumerator kFLEXPWM_FaultMask_3

FAULT3 (ch0) or FAULT7 (ch1)

enum _flexpwm_fault_clearing_mode

FlexPWM fault clearing mode selection.

Defines how fault conditions are cleared after a fault event.

Values:

enumerator kFLEXPWM_FaultClearingMode_Manual

Manual clearing - software must clear FSTS[FFLAGx]

enumerator kFLEXPWM_FaultClearingMode_Automatic

Automatic clearing when FAULTx de-asserts

enum _flexpwm_write_protect

FlexPWM write protection mode selection.

Values:

enumerator kFLEXPWM_WriteProtect_Off

Write protection off (default)

enumerator kFLEXPWM_WriteProtect_On

Write protection on

enumerator kFLEXPWM_WriteProtect_OffLocked
Write protection off and locked until chip reset

enumerator kFLEXPWM_WriteProtect_OnLocked
Write protection on and locked until chip reset

enum _flexpwm_stretch_prescaler
FlexPWM trigger signal stretch prescaler selection.

Stretch IPBus clock count prescaler for trigger signals including: mux0_trig, mux1_trig, out0_trig, out1_trig, pwma_trig, pwmb_trig

Values:

enumerator kFLEXPWM_StretchPrescaler_None
No stretch

enumerator kFLEXPWM_StretchPrescaler_2Clocks
Stretch for 2 IPBus clock periods

enumerator kFLEXPWM_StretchPrescaler_4Clocks
Stretch for 4 IPBus clock periods

enumerator kFLEXPWM_StretchPrescaler_8Clocks
Stretch for 8 IPBus clock periods

enum _flexpwm_trigger_mux_source
FlexPWM output trigger source selection for PWM_MUX_TRIG0/1 ports.

Selects which signal is routed to the PWM_MUX_TRIG0/1 output ports.

Values:

enumerator kFLEXPWM_TriggerMuxSource_GeneratedTrigger
Use PWM_OUT_TRIG0/1 (generated trigger signal)

enumerator kFLEXPWM_TriggerMuxSource_PWMOutput
Use PWM_A/PWM_B output directly

enum _flexpwm_trigger_frequency
FlexPWM output trigger frequency selection.

Controls the trigger output frequency when CTRL[LDFQ] is non-zero. Only takes effect when reload frequency divider is active (LDFQ > 0).

Values:

enumerator kFLEXPWM_TriggerFrequency_EveryCycle
Trigger every PWM cycle even if reload doesn't occur

enumerator kFLEXPWM_TriggerFrequency_OnReload
Trigger only on last cycle before reload opportunity

enum _flexpwm_output_trigger_mask

FlexPWM output trigger enable mask.

These flags can be OR'ed together to enable multiple trigger sources simultaneously. Used with outTriggerEnable field in flexpwm_output_trigger_config_t structure.

Values:

enumerator kFLEXPWM_OutputTriggerMask_VAL0

VAL0 match triggers PWM_OUT_TRIG0

enumerator kFLEXPWM_OutputTriggerMask_VAL1

VAL1 match triggers PWM_OUT_TRIG1

enumerator kFLEXPWM_OutputTriggerMask_VAL2

VAL2 match triggers PWM_OUT_TRIG0

enumerator kFLEXPWM_OutputTriggerMask_VAL3

VAL3 match triggers PWM_OUT_TRIG1

enumerator kFLEXPWM_OutputTriggerMask_VAL4

VAL4 match triggers PWM_OUT_TRIG0

enumerator kFLEXPWM_OutputTriggerMask_VAL5

VAL5 match triggers PWM_OUT_TRIG1

enum _flexpwm_capture_edge

FlexPWM input capture edge selection.

This enumeration defines the edge detection modes for input capture. The enum values directly map to hardware register bit values.

Values:

enumerator kFLEXPWM_CaptureEdge_Disabled

Disable capture (register bit value: 00b)

enumerator kFLEXPWM_CaptureEdge_Falling

Capture on falling edge (register bit value: 01b)

enumerator kFLEXPWM_CaptureEdge_Rising

Capture on rising edge (register bit value: 10b)

enumerator kFLEXPWM_CaptureEdge_Both

Capture on any edge (register bit value: 11b)

enum _flexpwm_capture_fifo_watermark

FlexPWM capture FIFO watermark selection.

This enumeration defines the FIFO watermark levels that determine when a watermark interrupt is triggered based on the number of valid samples in the FIFO.

Values:

enumerator kFLEXPWM_CaptureFifoWatermark_1
Trigger when FIFO has 1 or more samples (00b)

enumerator kFLEXPWM_CaptureFifoWatermark_2
Trigger when FIFO has 2 or more samples (01b)

enumerator kFLEXPWM_CaptureFifoWatermark_3
Trigger when FIFO has 3 or more samples (10b)

enumerator kFLEXPWM_CaptureFifoWatermark_4
Trigger when FIFO is full with 4 samples (11b)

enum _flexpwm_capture_input_select
FlexPWM capture input source selection.

This enumeration selects the source signal for input capture.

Values:

enumerator kFLEXPWM_CaptureInput_RawSignal
Use raw PWM input signal (register bit value: 0)

enumerator kFLEXPWM_CaptureInput_EdgeCounter
Use edge counter output (register bit value: 1). Used to reduce capture frequency by counting N edges

enum _flexpwm_capture_index
FlexPWM capture value index.

This enumeration defines the index for accessing capture value registers (CVAL0-5).

Note: Capture channel to CVAL register mapping (non-intuitive hardware mapping):

- Capture_X Edge0/Edge1 -> CVAL0/CVAL1 (and CVAL0CYC/CVAL1CYC)
- Capture_A Edge0/Edge1 -> CVAL2/CVAL3 (and CVAL2CYC/CVAL3CYC)
- Capture_B Edge0/Edge1 -> CVAL4/CVAL5 (and CVAL4CYC/CVAL5CYC)

Values:

enumerator kFLEXPWM_Capture_X_Edge0
CVAL0 - Capture_X Edge0

enumerator kFLEXPWM_Capture_X_Edge1
CVAL1 - Capture_X Edge1

enumerator kFLEXPWM_Capture_A_Edge0
CVAL2 - Capture_A Edge0

enumerator kFLEXPWM_Capture_A_Edge1
CVAL3 - Capture_A Edge1

enumerator kFLEXPWM_Capture_B_Edge0
CVAL4 - Capture_B Edge0

enumerator kFLEXPWM_Capture_B_Edge1
CVAL5 - Capture_B Edge1

enum _flexpwm_capture_channel
FlexPWM capture channel selection.

This enumeration defines the capture channel for enable/disable operations.

Values:

enumerator kFLEXPWM_Capture_A
Capture channel A (PWM_A)

enumerator kFLEXPWM_Capture_B
Capture channel B (PWM_B)

enumerator kFLEXPWM_Capture_X
Capture channel X (PWM_X)

enum _flexpwm_submodule_interrupt_enable
FlexPWM submodule interrupt enable flags.

These flags can be OR'ed together to enable multiple interrupt sources simultaneously. Use with *FLEXPWM_EnableSubmoduleInterrupts()* and *FLEXPWM_DisableSubmoduleInterrupts()*.

Values:

enumerator kFLEXPWM_Compare0InterruptEnable
VAL0 compare interrupt

enumerator kFLEXPWM_Compare1InterruptEnable
VAL1 compare interrupt

enumerator kFLEXPWM_Compare2InterruptEnable
VAL2 compare interrupt

enumerator kFLEXPWM_Compare3InterruptEnable
VAL3 compare interrupt

enumerator kFLEXPWM_Compare4InterruptEnable
VAL4 compare interrupt

enumerator kFLEXPWM_Compare5InterruptEnable
VAL5 compare interrupt

enumerator kFLEXPWM_CaptureX0InterruptEnable
Capture X0 interrupt

enumerator kFLEXPWM_CaptureX1InterruptEnable
Capture X1 interrupt

enumerator kFLEXPWM_CaptureB0InterruptEnable
Capture B0 interrupt

enumerator kFLEXPWM_CaptureB1InterruptEnable
Capture B1 interrupt

enumerator kFLEXPWM_CaptureA0InterruptEnable
Capture A0 interrupt

enumerator kFLEXPWM_CaptureA1InterruptEnable
Capture A1 interrupt

enumerator kFLEXPWM_ReloadInterruptEnable
Reload interrupt

enumerator kFLEXPWM_ReloadErrorInterruptEnable
Reload error interrupt

enum _flexpwm_submodule_status_flag
FlexPWM submodule status flags.

These flags represent the status of various events in a FlexPWM submodule. Use with *FLEXPWM_GetSubmoduleStatusFlags()* and *FLEXPWM_ClearSubmoduleStatusFlags()*.

Note: kFLEXPWM_RegisterUpdatedFlag is read-only and cannot be cleared by software.

Values:

enumerator kFLEXPWM_Compare0Flag
VAL0 compare flag

enumerator kFLEXPWM_Compare1Flag
VAL1 compare flag

enumerator kFLEXPWM_Compare2Flag
VAL2 compare flag

enumerator kFLEXPWM_Compare3Flag
VAL3 compare flag

enumerator kFLEXPWM_Compare4Flag
VAL4 compare flag

enumerator kFLEXPWM_Compare5Flag
VAL5 compare flag

enumerator kFLEXPWM_CaptureX0Flag
Capture X0 flag

enumerator kFLEXPWM_CaptureX1Flag
Capture X1 flag

enumerator kFLEXPWM_CaptureB0Flag
Capture B0 flag

enumerator kFLEXPWM_CaptureB1Flag
Capture B1 flag

enumerator kFLEXPWM_CaptureA0Flag
Capture A0 flag

enumerator kFLEXPWM_CaptureA1Flag
Capture A1 flag

enumerator kFLEXPWM_ReloadFlag
Reload flag

enumerator kFLEXPWM_ReloadErrorFlag
Reload error flag

enumerator kFLEXPWM_RegisterUpdatedFlag
Register updated flag (read-only)

enum _flexpwm_fault_interrupt_enable
FlexPWM fault interrupt enable flags.

These flags can be OR'ed together to enable multiple fault interrupt sources. Use with *FLEXPWM_EnableFaultInterrupts()* and *FLEXPWM_DisableFaultInterrupts()*.

Note: For dual-channel platforms (FSL_FEATURE_PWM_FAULT_CH_COUNT > 1): The same bit mask values are used for both fault channels:

- faultChannel = 0: Controls FAULT0-3
- faultChannel = 1: Controls FAULT4-7 The bit positions are the same, but the function parameter determines which fault channel is configured.

Values:

enumerator kFLEXPWM_Fault0InterruptEnable
FAULT0 (ch0) or FAULT4 (ch1) interrupt

enumerator kFLEXPWM_Fault1InterruptEnable
FAULT1 (ch0) or FAULT5 (ch1) interrupt

enumerator kFLEXPWM_Fault2InterruptEnable
FAULT2 (ch0) or FAULT6 (ch1) interrupt

enumerator kFLEXPWM_Fault3InterruptEnable

FAULT3 (ch0) or FAULT7 (ch1) interrupt

enum _flexpwm_fault_status_flag

FlexPWM fault status flags (FFLAG)

These flags represent the latched fault status (FFLAG bits in FSTS register). Use with *FLEXPWM_GetFaultStatusFlags()* and *FLEXPWM_ClearFaultStatusFlags()*.

Note: FFLAG characteristics:

- Write-1-to-clear: Software must write 1 to clear each flag
- Latched event: Set within 2 CPU cycles after FAULTx pin transitions to active state
- Historical record: Indicates a fault event has occurred (not current pin state)
- Interrupt capable: Can generate CPU interrupt requests when enabled
- Manual clearing: Does not auto-clear; requires explicit software action

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Note: To check the real-time, filtered hardware pin status (not the latched event), use *FLEXPWM_GetFaultFilteredPinStatusFlags()* to read FFPIN instead.

Note: For dual-channel platforms: The same bit mask values apply to both channels.

- faultChannel = 0: FAULT0-3 flags
- faultChannel = 1: FAULT4-7 flags

Values:

enumerator kFLEXPWM_Fault0Flag

FAULT0 (ch0) or FAULT4 (ch1) flag

enumerator kFLEXPWM_Fault1Flag

FAULT1 (ch0) or FAULT5 (ch1) flag

enumerator kFLEXPWM_Fault2Flag

FAULT2 (ch0) or FAULT6 (ch1) flag

enumerator kFLEXPWM_Fault3Flag

FAULT3 (ch0) or FAULT7 (ch1) flag

enum _flexpwm_fault_pin_status

FlexPWM filtered fault pin status (FFPIN - read-only)

These flags represent the real-time status of fault pins after filtering (FFPIN bits in FSTS register). Use with *FLEXPWM_GetFaultFilteredPinStatusFlags()* to check if external fault signals are currently active.

Note: FFPIN characteristics:

- Read-only: Cannot be written or cleared by software

- Real-time status: Reflects current state of filtered FAULTx pin (not historical)
- Polarity converted: Always shows active-high logic (1 = fault present)
- Filter output: Shows fault filter output, not raw pin state
- No interrupt: Does not directly generate interrupts (use FFLAG for interrupts)
- Filter delay: May remain high briefly after raw pin clears due to filter latency

Note: Key differences from FFLAG:

- FFLAG: Software-clearable latched flag (historical event - "a fault occurred")
- FFPIN: Read-only real-time status (current state - "fault is active now")

Note: For dual-channel platforms: The same bit positions apply to both channels.

- faultChannel = 0: FAULT0-3 pin status
- faultChannel = 1: FAULT4-7 pin status

Values:

enumerator kFLEXPWM_Fault0PinActive
FAULT0/4 pin active (filtered)

enumerator kFLEXPWM_Fault1PinActive
FAULT1/5 pin active (filtered)

enumerator kFLEXPWM_Fault2PinActive
FAULT2/6 pin active (filtered)

enumerator kFLEXPWM_Fault3PinActive
FAULT3/7 pin active (filtered)

enum _flexpwm_dma_capture_source
FlexPWM DMA capture source selection.
This enumeration defines the trigger source for DMA read requests from capture FIFOs.
Values:

enumerator kFLEXPWM_DMADisable
Read DMA requests disabled

enumerator kFLEXPWM_DMAFIFOWatermark
Exceeding FIFO watermark sets read DMA request

enumerator kFLEXPWM_DMALocalSync
Local sync sets read DMA request

enumerator kFLEXPWM_DMALocalReload
Local reload sets read DMA request

enum _flexpwm_dma_enable

FlexPWM DMA enable flags.

These flags are used with *FLEXPWM_EnableDMA()* and *FLEXPWM_DisableDMA()* to control individual DMA channel enables. Multiple flags can be ORed together.

Values:

enumerator kFLEXPWM_DMA_CaptureX0Enable

Capture X0 FIFO DMA enable (CX0DE)

enumerator kFLEXPWM_DMA_CaptureX1Enable

Capture X1 FIFO DMA enable (CX1DE)

enumerator kFLEXPWM_DMA_CaptureB0Enable

Capture B0 FIFO DMA enable (CB0DE)

enumerator kFLEXPWM_DMA_CaptureB1Enable

Capture B1 FIFO DMA enable (CB1DE)

enumerator kFLEXPWM_DMA_CaptureA0Enable

Capture A0 FIFO DMA enable (CA0DE)

enumerator kFLEXPWM_DMA_CaptureA1Enable

Capture A1 FIFO DMA enable (CA1DE)

enumerator kFLEXPWM_DMA_ValueWriteEnable

Value registers DMA write enable (VALDE)

typedef enum *_flexpwm_clock_source* flexpwm_clock_source_t

FlexPWM clock source selection.

typedef enum *_flexpwm_prescaler* flexpwm_prescaler_t

FlexPWM clock prescaler selection.

typedef enum *_flexpwm_load_mode* flexpwm_load_mode_t

FlexPWM load mode selection.

typedef enum *_flexpwm_reload_source* flexpwm_reload_source_t

FlexPWM reload source selection.

typedef enum *_flexpwm_init_source* flexpwm_init_source_t

FlexPWM counter initialization source selection.

typedef enum *_flexpwm_compare_mode* flexpwm_compare_mode_t

FlexPWM PWM compare mode selection.

typedef enum *_flexpwm_submodule_mask* flexpwm_submodule_mask_t

FlexPWM submodule mask for multi-submodule operations.

These flags can be OR'ed together to specify multiple submodules simultaneously. Used with functions that operate on multiple submodules at once.

typedef struct *_flexpwm_counter_config* flexpwm_counter_config_t

FlexPWM counter configuration structure.

typedef struct *_flexpwm_reload_config* flexpwm_reload_config_t

FlexPWM reload configuration structure.

typedef struct *_flexpwm_submodule_config* flexpwm_submodule_config_t

FlexPWM submodule configuration structure.

This structure defines the basic configuration parameters for a FlexPWM submodule, including clock source, prescaler, counter behavior, reload mechanism, and operating modes.

Note: This configuration writes to buffered registers. After calling *FLEXPWM_ConfigSubmodule()*, you must set MCTRL[LDOK] using a separate function to transfer the configuration to active registers.

Note: This function does not start the PWM counter. Use a separate API to enable the counter.

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typedef enum *_flexpwm_pwm_polarity* flexpwm_pwm_polarity_t

FlexPWM PWM output polarity selection.

typedef enum *_flexpwm_ipol_source* flexpwm_ipol_source_t

FlexPWM PWM output source selection for complementary mode.

typedef struct *_flexpwm_pwm_channel_config* flexpwm_pwm_channel_config_t

FlexPWM PWM channel configuration structure.

This structure defines the configuration for a PWM channel pair (PWM_A or PWM_B), including compare values, output polarity, and initial value.

typedef struct *_flexpwm_pwm_config* flexpwm_pwm_config_t

FlexPWM PWM configuration structure.

This structure defines the PWM output configuration for a FlexPWM submodule, including compare values, polarity, and operating mode (independent or complementary).

Note: For complementary mode: Only the selected channel (specified by ipolSource) needs to be configured. The other channel will be ignored by the hardware. For example, if ipolSource = kFLEXPWM_IPOL_PWM23, only pwma will be used.

Note: For independent mode: Both pwma and pwmb must be configured separately. The ipolSource field is ignored when complementary = false.

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typedef enum *_flexpwm_force_output_source* flexpwm_force_output_source_t

FlexPWM FORCE_OUT event source selection.

typedef enum *_flexpwm_force_pwm_source* flexpwm_force_pwm_source_t

FlexPWM PWM source selection for deadtime logic (DTSRCSEL)

typedef struct *_flexpwm_force_out_channel_config* flexpwm_force_out_channel_config_t

FlexPWM PWM channel force output configuration structure.

This structure defines the force output configuration for a PWM channel (PWM_A or PWM_B), including the source selection and software-controlled output value.

typedef struct *_flexpwm_force_out_config* flexpwm_force_out_config_t

FlexPWM force output configuration structure.

This structure defines the force output (FORCE_OUT event) configuration for a FlexPWM submodule, including the trigger source, PWM logical initial value, and PWM source selection.

typedef enum *_flexpwm_fault_output_behavior* flexpwm_fault_output_behavior_t

FlexPWM fault output behavior during fault condition.

Defines how PWM outputs respond when a fault is detected. Values map directly to SMxOCTRL[PWMAFS/PWMBFS/PWMXFS] bitfields.

typedef enum *_flexpwm_fault_mask* flexpwm_fault_mask_t

FlexPWM fault input mask for fault protection configuration.

These flags can be OR'ed together to configure multiple fault inputs simultaneously with the same protection parameters. Used with *FLEXPWM_ConfigFaultProtection()* function.

Note: For dual-channel platforms (FSL_FEATURE_PWM_FAULT_CH_COUNT > 1):

- When faultChannel = 0: Use kFLEXPWM_FaultMask_0/1/2/3 for FAULT0-3
- When faultChannel = 1: Use kFLEXPWM_FaultMask_0/1/2/3 for FAULT4-7 The enum values are the same, but the channel parameter determines which physical fault inputs are configured.

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typedef struct *_flexpwm_fault_output_config* flexpwm_fault_output_config_t

FlexPWM fault output configuration structure.

Configures fault protection for a single PWM output (PWM_A, PWM_B, or PWM_X). Supports both single-channel (FAULT0-3 only) and dual-channel (FAULT0-3 and FAULT4-7) platforms via conditional compilation. Can use flexpwm_fault_mask_t enum values (kFLEXPWM_FaultMask_0/1/2/3) and OR them together for multiple faults.

typedef struct *_flexpwm_fault_submodule_config* flexpwm_fault_submodule_config_t

FlexPWM fault submodule configuration structure.

Configures fault protection for all three PWM outputs (PWM_A, PWM_B, PWM_X) of a FlexPWM submodule. Includes fault disable mapping and output behavior for each output.

typedef enum *_flexpwm_fault_clearing_mode* flexpwm_fault_clearing_mode_t

FlexPWM fault clearing mode selection.

Defines how fault conditions are cleared after a fault event.

typedef struct *_flexpwm_fault_config* flexpwm_fault_config_t

FlexPWM fault protection configuration structure.

Configures global fault protection parameters for one fault channel. These settings apply to all submodules and their outputs that reference this channel. For platforms with dual fault channels (FAULT0-3 and FAULT4-7), configure each channel separately using *FLEXPWM_ConfigFaultProtection()*.

typedef struct *_flexpwm_fault_filter_config* flexpwm_fault_filter_config_t

FlexPWM fault filter configuration structure.

Configures input filter for fault protection pins to debounce electrical noise. The filter requires the input signal to be stable for N consecutive samples (where each sample is taken every T IPBus clock cycles) before reporting a fault. Helps avoid false fault triggers from noise on FAULTx pins.

typedef enum *_flexpwm_write_protect* flexpwm_write_protect_t

FlexPWM write protection mode selection.

typedef enum *_flexpwm_stretch_prescaler* flexpwm_stretch_prescaler_t

FlexPWM trigger signal stretch prescaler selection.

Stretch IPBus clock count prescaler for trigger signals including: mux0_trig, mux1_trig, out0_trig, out1_trig, pwma_trig, pwmb_trig

typedef enum *_flexpwm_trigger_mux_source* flexpwm_trigger_mux_source_t

FlexPWM output trigger source selection for PWM_MUX_TRIG0/1 ports.

Selects which signal is routed to the PWM_MUX_TRIG0/1 output ports.

typedef enum *_flexpwm_trigger_frequency* flexpwm_trigger_frequency_t

FlexPWM output trigger frequency selection.

Controls the trigger output frequency when CTRL[LDFQ] is non-zero. Only takes effect when reload frequency divider is active (LDFQ > 0).

typedef enum *_flexpwm_output_trigger_mask* flexpwm_output_trigger_mask_t

FlexPWM output trigger enable mask.

These flags can be OR'ed together to enable multiple trigger sources simultaneously. Used with outTriggerEnable field in flexpwm_output_trigger_config_t structure.

typedef struct *_flexpwm_output_trigger_config* flexpwm_output_trigger_config_t

FlexPWM output trigger configuration structure.

This structure defines the output trigger configuration for a FlexPWM submodule, including trigger source mapping from VAL registers, trigger frequency control, and output port routing.

Note: outTriggerEnable is a 6-bit mask corresponding to OUT_TRIG_EN[5:0], where each bit enables a trigger source from VAL0-5 register matches:

- bit[0]: VAL0 match triggers PWM_OUT_TRIG0
- bit[1]: VAL1 match triggers PWM_OUT_TRIG1
- bit[2]: VAL2 match triggers PWM_OUT_TRIG0
- bit[3]: VAL3 match triggers PWM_OUT_TRIG1

- bit[4]: VAL4 match triggers PWM_OUT_TRIG0
- bit[5]: VAL5 match triggers PWM_OUT_TRIG1 Multiple bits can be set to combine trigger sources (OR logic).

Note: triggerFrequency only takes effect when CTRL[LDFQ] is non-zero.

- false: Triggers output every PWM cycle even if reload doesn't occur
- true: Triggers output only on the last PWM cycle before a reload opportunity

---

typedef enum *_flexpwm_capture_edge* flexpwm_capture_edge_t

FlexPWM input capture edge selection.

This enumeration defines the edge detection modes for input capture. The enum values directly map to hardware register bit values.

typedef enum *_flexpwm_capture_fifo_watermark* flexpwm_capture_fifo_watermark_t

FlexPWM capture FIFO watermark selection.

This enumeration defines the FIFO watermark levels that determine when a watermark interrupt is triggered based on the number of valid samples in the FIFO.

typedef enum *_flexpwm_capture_input_select* flexpwm_capture_input_select_t

FlexPWM capture input source selection.

This enumeration selects the source signal for input capture.

typedef enum *_flexpwm_capture_index* flexpwm_capture_index_t

FlexPWM capture value index.

This enumeration defines the index for accessing capture value registers (CVAL0-5).

Note: Capture channel to CVAL register mapping (non-intuitive hardware mapping):

- Capture_X Edge0/Edge1 -> CVAL0/CVAL1 (and CVAL0CYC/CVAL1CYC)
- Capture_A Edge0/Edge1 -> CVAL2/CVAL3 (and CVAL2CYC/CVAL3CYC)
- Capture_B Edge0/Edge1 -> CVAL4/CVAL5 (and CVAL4CYC/CVAL5CYC)

---

typedef enum *_flexpwm_capture_channel* flexpwm_capture_channel_t

FlexPWM capture channel selection.

This enumeration defines the capture channel for enable/disable operations.

typedef struct *_flexpwm_capture_channel_config* flexpwm_capture_channel_config_t

FlexPWM single capture channel configuration structure.

This structure defines the configuration parameters for a single input capture channel.

typedef struct *_flexpwm_input_capture_config* flexpwm_input_capture_config_t

FlexPWM input capture configuration structure.

This structure contains the configuration for three independent input capture channels. Users can configure only the channels they need; unused channels should be left at default values.

Note: Capture channel to CVAL/CVALxCYC register mapping (important for reading capture values):

- captureA -> CVAL2/CVAL3 (CVAL2CYC/CVAL3CYC)
- captureB -> CVAL4/CVAL5 (CVAL4CYC/CVAL5CYC)
- captureX -> CVAL0/CVAL1 (CVAL0CYC/CVAL1CYC)

---

typedef struct *_flexpwm_capture_filter_channel_config* flexpwm_capture_filter_channel_config_t

FlexPWM capture filter channel configuration structure.

This structure defines the digital filter parameters for a single capture input pin.

typedef struct *_flexpwm_capture_filter_config* flexpwm_capture_filter_config_t

FlexPWM input capture filter configuration structure.

This structure contains the filter configuration for three independent capture input pins.

Note: Capture filter to register mapping:

- captureA -> SMxCAPTFILTA register
- captureB -> SMxCAPTFILTB register
- captureX -> SMxCAPTFILTX register

---

typedef enum *_flexpwm_dma_capture_source* flexpwm_dma_capture_source_t

FlexPWM DMA capture source selection.

This enumeration defines the trigger source for DMA read requests from capture FIFOs.

typedef struct *_flexpwm_dma_config* flexpwm_dma_config_t

FlexPWM DMA configuration structure.

This structure holds the DMA control strategy configuration. These settings should be configured during initialization and typically do not need to be modified at runtime.

uint32_t FLEXPWM_GetInstance(PWM_Type *base)

Get the instance for FlexPWM module.

Parameters

- base – FlexPWM base address

Returns

Instance number if valid base address is provided, otherwise returns *ARRAY_SIZE(s_flexpwmBases)*

status_t FLEXPWM_Init(PWM_Type *base)

Initialize the FlexPWM module.

This function initializes the FlexPWM peripheral by:

- Enabling clocks for all submodules (SM0-SM3)
- Releasing peripheral reset (if supported by platform)

After calling this function, the FlexPWM module is ready for configuration. Additional configuration functions (FLEXPWM_ConfigSubmodule, FLEXPWM_ConfigPWM, etc.) should be called to set up the desired PWM behavior.

Note: This function does not configure any PWM parameters. It only enables the peripheral.

Note: This function does not start PWM generation. Use *FLEXPWM_EnableSubmoduleCounter()* and *FLEXPWM_EnablePWMOutput()* to start PWM output.

Parameters

- base – FlexPWM peripheral base address.

Returns

kStatus_Success if initialization is successful. kStatus_InvalidArgument if the base address is invalid.

status_t FLEXPWM_DeInit(PWM_Type *base)

Deinitialize the FlexPWM module.

This function deinitializes the FlexPWM peripheral by:

- Disabling clocks for all submodules (SM0-SM3)
- Asserting peripheral reset (if supported by platform)

After calling this function, all FlexPWM registers are reset.

Note: To re-enable PWM operation, call *FLEXPWM_Init()* again.

Parameters

- base – FlexPWM peripheral base address.

Returns

kStatus_Success if deinitialization is successful. kStatus_InvalidArgument if the base address is invalid.

FLEXPWM_GET_FCTRL_REG(base, ch)

FLEXPWM_GET_FSTS_REG(base, ch)

FLEXPWM_GET_FFILT_REG(base, ch)

FLEXPWM_GET_FCTRL2_REG(base, ch)

struct __flexpwm_counter_config

#include <fsl_flexpwm.h> FlexPWM counter configuration structure.

Public Members

uint16_t initValue

Counter initial value (INIT register).

uint16_t modValue

Counter modulo value (VAL1 register). Defines the PWM period upper limit.

flexpwm_init_source_t initSource

Counter initialization source selection. Determines when the counter resets to initValue.

struct _flexpwm_reload_config

#include <fsl_flexpwm.h> FlexPWM reload configuration structure.

Public Members

flexpwm_load_mode_t loadMode

Register load mode selection.

- kFLEXPWM_LoadMode_Opportunity: Load at next reload opportunity (PWM cycle)
- kFLEXPWM_LoadMode_Immediate: Load immediately after LDOK is set

uint8_t loadFrequency

Load frequency divider (LDFQ field, 0-15). Buffered registers reload every (loadFrequency + 1) PWM cycles.

- 0: Every PWM cycle
- 1: Every 2 PWM cycles
- 15: Every 16 PWM cycles

bool enableHalfCycleReload

Enable reload at half-cycle point (VAL0 match).

- true: Reload can occur at VAL0 match
- false: No reload at half-cycle

bool enableFullCycleReload

Enable reload at full-cycle point (VAL1 match).

- true: Reload can occur at VAL1 match
- false: No reload at full-cycle

flexpwm_reload_source_t reloadSource

Reload signal source selection.

- kFLEXPWM_ReloadSource_LocalReload: Use local reload signal
- kFLEXPWM_ReloadSource_MasterReload: Use master reload from submodule 0

uint16_t halfCycleValue

Half-cycle reload point (VAL0 register). This value determines when half-cycle reload occurs. Note: Does not need to be exactly half the PWM period.

struct _flexpwm_submodule_config

#include <fsl_flexpwm.h> FlexPWM submodule configuration structure.

This structure defines the basic configuration parameters for a FlexPWM submodule, including clock source, prescaler, counter behavior, reload mechanism, and operating modes.

Note: This configuration writes to buffered registers. After calling *FLEXPWM_ConfigSubmodule()*, you must set MCTRL[LDOK] using a separate function to transfer the configuration to active registers.

Note: This function does not start the PWM counter. Use a separate API to enable the counter.

Public Members

flexpwm_clock_source_t clockSource

Clock source for the submodule PWM counter.

flexpwm_prescaler_t prescaler

Clock prescaler divider.

flexpwm_counter_config_t counterConfig

Counter initialization and behavior configuration.

flexpwm_reload_config_t reloadConfig

Register reload mechanism configuration.

bool enableDebugMode

PWM behavior in Debug mode.

- true: PWM continues running when MCU enters Debug mode
- false: PWM stops when MCU enters Debug mode

struct __flexpwm__pwm__channel__config

#include <fsl_flexpwm.h> FlexPWM PWM channel configuration structure.

This structure defines the configuration for a PWM channel pair (PWM_A or PWM_B), including compare values, output polarity, and initial value.

Public Members

uint16_t compareValue__ON

Compare value that defines the PWM turn-on edge (in normal polarity). Mapping per channel:

- PWM_A: written to VAL2
- PWM_B: written to VAL4
- PWM_X: written to VAL0

uint16_t compareValue__OFF

Compare value that defines the PWM turn-off edge (in normal polarity). Mapping per channel:

- PWM_A: written to VAL3

- PWM_B: written to VAL5
- PWM_X: written to VAL1

flexpwm_pwm_polarity_t polarity

Output polarity.

- kFLEXPWM_Polarity_ActiveLow: PWM signal is inverted (active low)
- kFLEXPWM_Polarity_ActiveHigh: PWM signal is normal (active high)

struct __flexpwm__pwm__config

#include <fsl_flexpwm.h> FlexPWM PWM configuration structure.

This structure defines the PWM output configuration for a FlexPWM submodule, including compare values, polarity, and operating mode (independent or complementary).

Note: For complementary mode: Only the selected channel (specified by ipolSource) needs to be configured. The other channel will be ignored by the hardware. For example, if ipolSource = kFLEXPWM_IPOL_PWM23, only pwma will be used.

Note: For independent mode: Both pwma and pwmb must be configured separately. The ipolSource field is ignored when complementary = false.

Public Members

flexpwm_pwm_channel_config_t pwma

PWM_A (PWM23) channel configuration

flexpwm_pwm_channel_config_t pwmb

PWM_B (PWM45) channel configuration

bool complementary

Operating mode.

- true: Complementary mode (PWM_A and PWM_B form a complementary pair)
- false: Independent mode (PWM_A and PWM_B are independent channels)

flexpwm_ipol_source_t ipolSource

MCTRL[IPOL] - Select which channel pair as complementary source. Only used when complementary = true.

- kFLEXPWM_IPOL_PWM23: Use PWM23 as source
- kFLEXPWM_IPOL_PWM45: Use PWM45 as source

struct __flexpwm__force__out__channel__config

#include <fsl_flexpwm.h> FlexPWM PWM channel force output configuration structure.

This structure defines the force output configuration for a PWM channel (PWM_A or PWM_B), including the source selection and software-controlled output value.

Public Members

flexpwm_force_pwm_source_t source

PWM source selection for this channel (DTSRCSEL).

bool softwareValue

When source=kFLEXPWM_ForcePwmSource_Software, this value (0 or 1) is output to deadtime logic (SWCOUT).

struct __flexpwm_force_out_config

#include <fsl_flexpwm.h> FlexPWM force output configuration structure.

This structure defines the force output (FORCE_OUT event) configuration for a FlexPWM submodule, including the trigger source, PWM logical initial value, and PWM source selection.

Public Members

flexpwm_force_output_source_t forceSource

FORCE_OUT trigger source (CTRL2[FORCE_SEL]).

flexpwm_force_out_channel_config_t pwma

PWM_A (PWM23) force output configuration.

flexpwm_force_out_channel_config_t pwmb

PWM_B (PWM45) force output configuration.

bool pwma_initialValue

PWM_A (PWM23) logical initial value in normal polarity.

- true: PWM_A output starts at logic 1
- false: PWM_A output starts at logic 0

bool pwmb_initialValue

PWM_B (PWM45) logical initial value in normal polarity.

- true: PWM_B output starts at logic 1
- false: PWM_B output starts at logic 0

bool pwmx_initialValue

PWM_X logical initial value in normal polarity.

- true: PWM_X output starts at logic 1
- false: PWM_X output starts at logic 0

struct __flexpwm_fault_output_config

#include <fsl_flexpwm.h> FlexPWM fault output configuration structure.

Configures fault protection for a single PWM output (PWM_A, PWM_B, or PWM_X). Supports both single-channel (FAULT0-3 only) and dual-channel (FAULT0-3 and FAULT4-7) platforms via conditional compilation. Can use flexpwm_fault_mask_t enum values (kFLEXPWM_FaultMask_0/1/2/3) and OR them together for multiple faults.

Public Members

uint16_t disableMask_ch0

Fault disable mask for channel 0 (FAULT0-3). Each bit selects one fault input:

- bit[0] = FAULT0
- bit[1] = FAULT1
- bit[2] = FAULT2
- bit[3] = FAULT3 Maps to SMxDISMAP[0] register.

flexpwm_fault_output_behavior_t outputBehavior

Output behavior when fault is detected Maps to SMxOCTRL[PWMAFS/PWMBFS/PWMXFS].

struct _flexpwm_fault_submodule_config

#include <fsl_flexpwm.h> FlexPWM fault submodule configuration structure.

Configures fault protection for all three PWM outputs (PWM_A, PWM_B, PWM_X) of a FlexPWM submodule. Includes fault disable mapping and output behavior for each output.

Public Members

flexpwm_fault_output_config_t pwma

PWM_A (PWM23) fault configuration. Controls which faults disable PWM_A output and how PWM_A behaves during fault.

flexpwm_fault_output_config_t pwmb

PWM_B (PWM45) fault configuration. Controls which faults disable PWM_B output and how PWM_B behaves during fault.

flexpwm_fault_output_config_t pwmx

PWM_X fault configuration. Controls which faults disable PWM_X output and how PWM_X behaves during fault.

struct _flexpwm_fault_config

#include <fsl_flexpwm.h> FlexPWM fault protection configuration structure.

Configures global fault protection parameters for one fault channel. These settings apply to all submodules and their outputs that reference this channel. For platforms with dual fault channels (FAULT0-3 and FAULT4-7), configure each channel separately using *FLEXPWM_ConfigFaultProtection()*.

Public Members

bool faultInputActiveLevel

FAULTx input active level (FCTRL[FLVL])

- false: Logic 0 on FAULTx indicates fault (active low)
- true: Logic 1 on FAULTx indicates fault (active high)

flexpwm_fault_clearing_mode_t faultClearingMode

Fault clearing mode (FCTRL[FAUTO])

bool enableSafetyMode

Safety Mode (FCTRL[FSAFE]) Only useful for Manual fault clearing mode

- false: Normal mode (PWM outputs enabled when FFLAG clears)
- true: Safe mode (PWM outputs enabled only when both FFLAG and FFPIN are clear)

bool enableFullCycleRecovery

Full Cycle Recovery (FSTS[FFULL])

- true: PWM outputs can be re-enabled at PWM full cycle start
- false: No re-enable at full cycle

bool enableHalfCycleRecovery

Half Cycle Recovery (FSTS[FHALF])

- true: PWM outputs can be re-enabled at PWM half cycle start
- false: No re-enable at half cycle

bool enableCombinatorialPath

Combinational Path Control (FCTRL2[NOCOMB])

- true: Combinational path active - fault input directly disables PWM outputs (fastest response)
- false: Combinational path disabled - only latched fault signal disables PWM outputs (adds latency)

struct _flexpwm_fault_filter_config

#include <fsl_flexpwm.h> FlexPWM fault filter configuration structure.

Configures input filter for fault protection pins to debounce electrical noise. The filter requires the input signal to be stable for N consecutive samples (where each sample is taken every T IPBus clock cycles) before reporting a fault. Helps avoid false fault triggers from noise on FAULTx pins.

Public Members

uint8_t filterPeriod

Fault Filter Period (FFILT[FILT_PER]) Sampling period in IPBus clock cycles. Range: 0-255

- 0: Input filter bypassed
- N: FAULTx sampled every N IPBus cycles

uint8_t filterCount

Fault Filter Count (FFILT[FILT_CNT]) Number of consecutive stable samples required to accept input transition. Range: 0-7 (actual samples = value + 3)

- 0: 3 samples

- 1: 4 samples
- 7: 10 samples

bool enableGlitchStretch

Fault Glitch Stretching (FFILT[GSTR])

- false: Glitch stretching disabled
- true: Input fault signals stretched to min 2 IPBus cycles Prevents false triggers from narrow glitches

struct __flexpwm_output_trigger_config

#include <fsl_flexpwm.h> FlexPWM output trigger configuration structure.

This structure defines the output trigger configuration for a FlexPWM submodule, including trigger source mapping from VAL registers, trigger frequency control, and output port routing.

Note: outTriggerEnable is a 6-bit mask corresponding to OUT_TRIG_EN[5:0], where each bit enables a trigger source from VAL0-5 register matches:

- bit[0]: VAL0 match triggers PWM_OUT_TRIG0
- bit[1]: VAL1 match triggers PWM_OUT_TRIG1
- bit[2]: VAL2 match triggers PWM_OUT_TRIG0
- bit[3]: VAL3 match triggers PWM_OUT_TRIG1
- bit[4]: VAL4 match triggers PWM_OUT_TRIG0
- bit[5]: VAL5 match triggers PWM_OUT_TRIG1 Multiple bits can be set to combine trigger sources (OR logic).

Note: triggerFrequency only takes effect when CTRL[LDFQ] is non-zero.

- false: Triggers output every PWM cycle even if reload doesn't occur
- true: Triggers output only on the last PWM cycle before a reload opportunity

---

Public Members

uint16_t outTriggerEnable

Output trigger enable mask (OUT_TRIG_EN[5:0]). Bit mask for VAL0-5 trigger sources. OR'ed combination of flexpwm_output_trigger_mask_t Example: 0x05 enables VAL0 and VAL2 for TRIG0.

flexpwm_trigger_mux_source_t muxTrig0Source

PWM_MUX_TRIG0 port source selection (PWAOT0).

- kFLEXPWM_TriggerMuxSource_GeneratedTrigger: Route PWM_OUT_TRIG0 signal
- kFLEXPWM_TriggerMuxSource_PWMOutput: Route PWM_A output directly

flexpwm_trigger_mux_source_t muxTrig1Source

PWM_MUX_TRIG1 port source selection (PWBOT1).

- kFLEXPWM_TriggerMuxSource_GeneratedTrigger: Route PWM_OUT_TRIG1 signal
- kFLEXPWM_TriggerMuxSource_PWMOutput: Route PWM_B output directly

flexpwm_trigger_frequency_t triggerFrequency

Trigger frequency control (TRGFRQ). Controls trigger output frequency when CTRL[LDFQ] > 0.

- kFLEXPWM_TriggerFrequency_EveryCycle: Trigger every PWM cycle
- kFLEXPWM_TriggerFrequency_OnReload: Trigger only on last cycle before reload

flexpwm_stretch_prescaler_t stretchPrescaler

Trigger signal stretch prescaler (MCTRL2[STRETCH_CNT_PRSC]). Stretches trigger signal pulse width by specified IPBus clock cycles.

struct __flexpwm_capture_channel_config

#include <fsl_flexpwm.h> FlexPWM single capture channel configuration structure.

This structure defines the configuration parameters for a single input capture channel.

Public Members

flexpwm_capture_edge_t edge0

Edge0 capture edge selection

flexpwm_capture_edge_t edge1

Edge1 capture edge selection

bool oneshot

Capture mode.

- true: One-shot mode
- false: Free-running mode

flexpwm_capture_input_select_t inputSelect

Input signal source selection.

- kFLEXPWM_CaptureInput_RawSignal: Raw PWM input
- kFLEXPWM_CaptureInput_EdgeCounter: Edge counter output

bool enableEdgeCounter

Edge counter enable control.

- true: Enable edge counter (EDGCNT_EN = 1)
- false: Disable edge counter (EDGCNT_EN = 0)

uint8_t edgeCompareValue

Edge counter compare value (0-255). Capture occurs when edge count reaches this value. Only valid when enableEdgeCounter = true

flexpwm_capture_fifo_watermark_t fifoWatermark

FIFO watermark level

struct __flexpwm_input_capture_config

#include <fsl_flexpwm.h> FlexPWM input capture configuration structure.

This structure contains the configuration for three independent input capture channels. Users can configure only the channels they need; unused channels should be left at default values.

Note: Capture channel to CVAL/CVALxCYC register mapping (important for reading capture values):

- captureA -> CVAL2/CVAL3 (CVAL2CYC/CVAL3CYC)
- captureB -> CVAL4/CVAL5 (CVAL4CYC/CVAL5CYC)
- captureX -> CVAL0/CVAL1 (CVAL0CYC/CVAL1CYC)

Public Members

flexpwm_capture_channel_config_t captureA

Capture_A (PWM_A) channel configuration

flexpwm_capture_channel_config_t captureB

Capture_B (PWM_B) channel configuration

flexpwm_capture_channel_config_t captureX

Capture_X (PWM_X) channel configuration

struct __flexpwm_capture_filter_channel_config

#include <fsl_flexpwm.h> FlexPWM capture filter channel configuration structure.

This structure defines the digital filter parameters for a single capture input pin.

Public Members

uint8_t filterPeriod

Filter sampling period in IPBus clock cycles (0-255).

- 0: Bypass filter (default)
- Non-zero: Enable filter with specified sampling period

uint8_t filterCount

Number of consecutive consistent samples required (0-7). Actual sample count = filterCount + 3 (i.e., 3-10 samples)

struct _flexpwm_capture_filter_config

#include <fsl_flexpwm.h> FlexPWM input capture filter configuration structure.

This structure contains the filter configuration for three independent capture input pins.

Note: Capture filter to register mapping:

- captureA -> SMxCAPTFILTA register
- captureB -> SMxCAPTFILTB register
- captureX -> SMxCAPTFILTX register

Public Members

flexpwm_capture_filter_channel_config_t captureA

Capture_A filter configuration

flexpwm_capture_filter_channel_config_t captureB

Capture_B filter configuration

flexpwm_capture_filter_channel_config_t captureX

Capture_X filter configuration

struct _flexpwm_dma_config

#include <fsl_flexpwm.h> FlexPWM DMA configuration structure.

This structure holds the DMA control strategy configuration. These settings should be configured during initialization and typically do not need to be modified at runtime.

Public Members

flexpwm_dma_capture_source_t captureSource

Capture DMA enable source selection (CAPTDE[7:6])

bool fifoWatermarkAND

FIFO watermark AND/OR control (FAND).

- true: Selected FIFO watermarks are ANDed
- false: Selected FIFO watermarks are ORed

2.33 FREQME: Frequency Measurement

2.34 GLIKEY

2.35 GLIKEY

Values:

enumerator kStatus_GLIKEY_LockedError
GLIKEY status for locked SFR registers (unexpected) .

enumerator kStatus_GLIKEY_NotLocked
GLIKEY status for unlocked SFR registers.

enumerator kStatus_GLIKEY_Locked
GLIKEY status for locked SFR registers.

enumerator kStatus_GLIKEY_DisabledError
GLIKEY status for disabled error.

FSL_GLIKEY_DRIVER_VERSION
Defines GLIKEY driver version 2.0.1.

Change log:

- Version 2.0.1
  - Implement INIT state recovery from the LOCKED state after a reset when the previous index was locked.
- Version 2.0.0
  - Initial version

GLIKEY_CODEWORD_STEP1

GLIKEY_CODEWORD_STEP2

GLIKEY_CODEWORD_STEP3

GLIKEY_CODEWORD_STEP4

GLIKEY_CODEWORD_STEP5

GLIKEY_CODEWORD_STEP6

GLIKEY_CODEWORD_STEP7

GLIKEY_CODEWORD_STEP_EN

GLIKEY_FSM_WR_DIS

GLIKEY_FSM_INIT

GLIKEY_FSM_STEP1

GLIKEY_FSM_STEP2

GLIKEY_FSM_STEP3

GLIKEY_FSM_STEP4

GLIKEY_FSM_LOCKED

GLIKEY_FSM_WR_EN

GLIKEY_FSM_SSR_RESET

uint32_t GLIKEY_GetStatus(GLIKEY_Type *base)

Retreives the current status of Glikey.

Parameters

- base – **[in]** The base address of the Glikey instance

Returns

Glikey status information

status_t GLIKEY_IsLocked(GLIKEY_Type *base)

Get if Glikey is locked.

This operation returns the locking status of Glikey.

Return values

- kStatus_GLIKEY_Locked – if locked
- kStatus_GLIKEY_NotLocked – if unlocked

Returns

Status

status_t GLIKEY_CheckLock(GLIKEY_Type *base)

Check if Glikey is locked.

This operation returns the locking status of Glikey.

Return values

- kStatus_GLIKEY_LockedError – if locked
- kStatus_GLIKEY_NotLocked – if unlocked

Returns

Status kStatus_Success if success

status_t GLIKEY_SyncReset(GLIKEY_Type *base)

Perform a synchronous reset of Glikey.

This function performs a synchrounous reset of the Glikey. This results in:

- Glikey will return to the INIT state, unless it is in the LOCK state

Parameters

- base – **[in]** The base address of the Glikey instance

Returns

Status kStatus_Success if success Possible errors: kStatus_GLIKEY_LockedError

status_t GLIKEY_SetIntEnable(GLIKEY_Type *base, uint32_t value)

Set interrupt enable flag of Glikey.

Parameters

- base – **[in]** The base address of the Glikey instance
- value – **[in]** Value to set the interrupt enable flag to, see #[TODO: add reference to constants]

Returns

Status kStatus_Success if success Possible errors: kStatus_GLIKEY_LockedError

status_t GLIKEY_GetIntEnable(GLIKEY_Type *base, uint32_t *value)

Get interrupt enable flag of Glikey.

Parameters

- base – **[in]** The base address of the Glikey instance
- value – **[out]** Pointer which will be filled with the interrupt enable status, see #[TODO: add reference to constants]

Returns

Status kStatus_Success if success

status_t GLIKEY_ClearIntStatus(GLIKEY_Type *base)

Clear the interrupt status flag of Glikey.

Parameters

- base – **[in]** The base address of the Glikey instance

Returns

Status kStatus_Success if success Possible errors: kStatus_GLIKEY_LockedError

status_t GLIKEY_SetIntStatus(GLIKEY_Type *base)

Set the interrupt status flag of Glikey.

Parameters

- base – **[in]** The base address of the Glikey instance

Returns

Status kStatus_Success if success Possible errors: kStatus_GLIKEY_LockedError

status_t GLIKEY_Lock(GLIKEY_Type *base)

Lock Glikey SFR (Special Function Registers) interface.

This operation locks the Glikey SFR interface if it is not locked yet.

Parameters

- base – **[in]** The base address of the Glikey instance

Returns

Status kStatus_Success if success

status_t GLIKEY_LockIndex(GLIKEY_Type *base)

Lock Glikey index.

This operation is used to lock a Glikey index. It can only be executed from the WR_EN state, executing it from any other state will result in Glikey entering WR_DIS state. When this happens Glikey requires a reset (synchrous or asynchronous) to go back to INIT state. If the Glikey SFR lock is active this operation will return an error.

Parameters

- base – **[in]** The base address of the Glikey instance

Returns

Status kStatus_Success if success Possible errors: kStatus_GLIKEY_LockedError, kStatus_GLIKEY_DisabledError

status_t GLIKEY_IsIndexLocked(GLIKEY_Type *base, uint32_t index)

Check if Glikey index is locked.

This operation returns the locking status of Glikey index.

Parameters

- base – **[in]** The base address of the Glikey instance
- index – **[in]** The index of the Glikey instance

Returns

kStatus_GLIKEY_Locked if locked, kStatus_GLIKEY_NotLocked if unlocked Possible errors: kStatus_Fail

status_t GLIKEY_StartEnable(GLIKEY_Type *base, uint32_t index)

Start Glikey enable.

This operation is used to set a new index and start a the sequence to enable it. It needs to be started from the INIT state. If the new index is already locked Glikey will go to LOCKED state, otherwise it will go to STEP1 state. If this operation is used when Glikey is in any state other than INIT Glikey will go to WR_DIS state. It can only recover from this state through a reset (synchrounous or asyncrhonous). If the Glikey SFR lock is active this operation will return an error.

Parameters

- base – **[in]** The base address of the Glikey instance
- index – **[in]** The index of the Glikey instance

Returns

Status kStatus_Success if success Possible errors: kStatus_GLIKEY_LockedError, kStatus_Fail

status_t GLIKEY_ContinueEnable(GLIKEY_Type *base, uint32_t codeword)

Continue Glikey enable.

This operation is used to progress through the different states of the state machine, starting from STEP1 until the state WR_EN is reached. Each next state of the state machine can only be reached by providing the right codeword to this function. If anything goes wrong the state machine will go to WR_DIS state and can only recover from it through a reset (synchrous or asynchronous). If the Glikey SFR lock is active this operation will return an error.

Parameters

- base – **[in]** The base address of the Glikey instance
- codeword – **[in]** Encoded word for progressing to next FSM state (see GLIKEY_CODEWORD_STEPx/EN)

Returns

Status kStatus_Success if success Possible errors: kStatus_GLIKEY_LockedError, kStatus_Fail, kStatus_GLIKEY_DisabledError

status_t GLIKEY_EndOperation(GLIKEY_Type *base)

End Glikey operation.

This operation is used to end a Glikey operation. It can only be executed from the WR_EN, LOCKED and RESET states. Executing it from any other state will result in Glikey entering WR_DIS state. When this happens Glikey requires a reset (synchrous or asynchronous) to go back to INIT state. After this operation Glikey will go to INIT state or stay in LOCKED state when the index was locked. If the Glikey SFR lock is active this operation will return an error.

Parameters

- base – **[in]** The base address of the Glikey instance

Returns
A code-flow protected error code (see nxpCsslFlowProtection)

Returns
Status kStatus_Success if success, kStatus_GLIKEY_Locked if index is still locked Possible errors: kStatus_GLIKEY_LockedError, kStatus_GLIKEY_DisabledError

status_t GLIKEY_ResetIndex(GLIKEY_Type *base, uint32_t index)

Reset Glikey index.

This operation is used to reset a Glikey index. It can only be executed from the INIT state, executing it from any other state will result in Glikey entering WR_DIS state. When this happens Glikey requires a reset (synchrous or asynchronous) to go back to INIT state. If the Glikey SFR lock is active or the index is locked this operation will return an error.

Returns
A code-flow protected error code (see nxpCsslFlowProtection)

Returns
Status kStatus_Success if success, kStatus_GLIKEY_Locked if index is still locked Possible errors: kStatus_GLIKEY_LockedError, kStatus_GLIKEY_DisabledError

2.36 GPIO: General-Purpose Input/Output Driver

FSL_GPIO_DRIVER_VERSION

GPIO driver version.

enum _gpio_pin_direction

GPIO direction definition.

Values:

enumerator kGPIO_DigitalInput

Set current pin as digital input

enumerator kGPIO_DigitalOutput

Set current pin as digital output

enum _gpio_checker_attribute

GPIO checker attribute.

Values:

enumerator kGPIO_UsernonsecureRWUsersecureRWPrivilegedsecureRW
User nonsecure:Read+Write; User Secure:Read+Write; Privileged Secure:Read+Write

enumerator kGPIO_UsernonsecureRUsersecureRWPrivilegedsecureRW
User nonsecure:Read; User Secure:Read+Write; Privileged Secure:Read+Write

enumerator kGPIO_UsernonsecureNUsersecureRWPrivilegedsecureRW
User nonsecure:None; User Secure:Read+Write; Privileged Secure:Read+Write

enumerator kGPIO_UsernonsecureRUsersecureRPrivilegedsecureRW
User nonsecure:Read; User Secure:Read; Privileged Secure:Read+Write

enumerator kGPIO_UsernonsecureNUsersecureRPrivilegedsecureRW
User nonsecure:None; User Secure:Read; Privileged Secure:Read+Write

enumerator kGPIO_UsernonsecureNUsersecureNPrivilegedsecureRW
User nonsecure:None; User Secure:None; Privileged Secure:Read+Write

enumerator kGPIO_UsernonsecureNUsersecureNPrivilegedsecureR
User nonsecure:None; User Secure:None; Privileged Secure:Read

enumerator kGPIO_UsernonsecureNUsersecureNPrivilegedsecureN
User nonsecure:None; User Secure:None; Privileged Secure:None

enumerator kGPIO_IgnoreAttributeCheck
Ignores the attribute check

enum _gpio_interrupt_config
Configures the interrupt generation condition.
Values:

enumerator kGPIO_InterruptStatusFlagDisabled
Interrupt status flag is disabled.

enumerator kGPIO_DMARisingEdge
ISF flag and DMA request on rising edge.

enumerator kGPIO_DMAFallingEdge
ISF flag and DMA request on falling edge.

enumerator kGPIO_DMAEitherEdge
ISF flag and DMA request on either edge.

enumerator kGPIO_FlagRisingEdge
Flag sets on rising edge.

enumerator kGPIO_FlagFallingEdge
Flag sets on falling edge.

enumerator kGPIO_FlagEitherEdge
Flag sets on either edge.

enumerator kGPIO_InterruptLogicZero
Interrupt when logic zero.

enumerator kGPIO_InterruptRisingEdge
Interrupt on rising edge.

enumerator kGPIO_InterruptFallingEdge
Interrupt on falling edge.

enumerator kGPIO_InterruptEitherEdge
Interrupt on either edge.

enumerator kGPIO_InterruptLogicOne
Interrupt when logic one.

enumerator kGPIO_ActiveHighTriggerOutputEnable
Enable active high-trigger output.

enumerator kGPIO_ActiveLowTriggerOutputEnable
Enable active low-trigger output.

enum _gpio_interrupt_selection
Configures the selection of interrupt/DMA request/trigger output.
Values:

enumerator kGPIO_InterruptOutput0
Interrupt/DMA request/trigger output 0.

enumerator kGPIO_InterruptOutput1
Interrupt/DMA request/trigger output 1.

enum gpio_pin_interrupt_control_t
GPIO pin and interrupt control.
Values:

enumerator kGPIO_PinControlNonSecure
Pin Control Non-Secure.

enumerator kGPIO_InterruptControlNonSecure
Interrupt Control Non-Secure.

enumerator kGPIO_PinControlNonPrivilege
Pin Control Non-Privilege.

enumerator kGPIO_InterruptControlNonPrivilege
Interrupt Control Non-Privilege.

typedef enum *_gpio_pin_direction* gpio_pin_direction_t
GPIO direction definition.

typedef enum *_gpio_checker_attribute* gpio_checker_attribute_t
GPIO checker attribute.

typedef struct *_gpio_pin_config* gpio_pin_config_t
The GPIO pin configuration structure.

Each pin can only be configured as either an output pin or an input pin at a time. If configured as an input pin, leave the outputConfig unused. Note that in some use cases, the corresponding port property should be configured in advance with the *PORT_SetPinConfig()*.

typedef enum *_gpio_interrupt_config* gpio_interrupt_config_t
Configures the interrupt generation condition.

typedef enum *_gpio_interrupt_selection* gpio_interrupt_selection_t
Configures the selection of interrupt/DMA request/trigger output.

typedef struct *_gpio_version_info* gpio_version_info_t
GPIO version information.

GPIO_FIT_REG(value)

struct _gpio_pin_config
#include <fsl_gpio.h> The GPIO pin configuration structure.

Each pin can only be configured as either an output pin or an input pin at a time. If configured as an input pin, leave the outputConfig unused. Note that in some use cases, the corresponding port property should be configured in advance with the *PORT_SetPinConfig()*.

Public Members

gpio_pin_direction_t pinDirection
GPIO direction, input or output

uint8_t outputLogic
Set a default output logic, which has no use in input

struct _gpio_version_info
#include <fsl_gpio.h> GPIO version information.

Public Members

uint16_t feature
Feature Specification Number.

uint8_t minor
Minor Version Number.

uint8_t major
Major Version Number.

2.37 GPIO Driver

void GPIO_PortInit(GPIO_Type *base)
Initializes the GPIO peripheral.

This function ungates the GPIO clock.

Parameters

- base – GPIO peripheral base pointer.

void GPIO_PortDenit(GPIO_Type *base)
Denitializes the GPIO peripheral.

Parameters

- base – GPIO peripheral base pointer.

void GPIO_PinInit(GPIO_Type *base, uint32_t pin, const *gpio_pin_config_t* *config)
Initializes a GPIO pin used by the board.

To initialize the GPIO, define a pin configuration, as either input or output, in the user file. Then, call the *GPIO_PinInit()* function.

This is an example to define an input pin or an output pin configuration.

```
Define a digital input pin configuration,
gpio_pin_config_t config =
{
  kGPIO_DigitalInput,
  0,
}
Define a digital output pin configuration,
gpio_pin_config_t config =
{
  kGPIO_DigitalOutput,
  0,
}
```

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- pin – GPIO port pin number
- config – GPIO pin configuration pointer

void GPIO_GetVersionInfo(GPIO_Type *base, *gpio_version_info_t* *verInfo)
Get GPIO version information.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- verInfo – GPIO version information

static inline void GPIO_SecurePrivilegeLock(GPIO_Type *base, *gpio_pin_interrupt_control_t* mask)

lock or unlock secure privilege.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – pin or interrupt macro

static inline void GPIO_EnablePinControlNonSecure(GPIO_Type *base, uint32_t mask)

Enable Pin Control Non-Secure.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro

static inline void GPIO_DisablePinControlNonSecure(GPIO_Type *base, uint32_t mask)

Disable Pin Control Non-Secure.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro

static inline void GPIO_EnablePinControlNonPrivilege(GPIO_Type *base, uint32_t mask)

Enable Pin Control Non-Privilege.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro

static inline void GPIO_DisablePinControlNonPrivilege(GPIO_Type *base, uint32_t mask)

Disable Pin Control Non-Privilege.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro

static inline void GPIO_EnableInterruptControlNonSecure(GPIO_Type *base, uint32_t mask)

Enable Interrupt Control Non-Secure.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro

static inline void GPIO_DisableInterruptControlNonSecure(GPIO_Type *base, uint32_t mask)

Disable Interrupt Control Non-Secure.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro

static inline void GPIO_EnableInterruptControlNonPrivilege(GPIO_Type *base, uint32_t mask)

Enable Interrupt Control Non-Privilege.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro

static inline void GPIO_DisableInterruptControlNonPrivilege(GPIO_Type *base, uint32_t mask)
Disable Interrupt Control Non-Privilege.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro

static inline void GPIO_PortInputEnable(GPIO_Type *base, uint32_t mask)
Enable port input.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro

static inline void GPIO_PortInputDisable(GPIO_Type *base, uint32_t mask)
Disable port input.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro

static inline void GPIO_PinWrite(GPIO_Type *base, uint32_t pin, uint8_t output)
Sets the output level of the multiple GPIO pins to the logic 1 or 0.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- pin – GPIO pin number
- output – GPIO pin output logic level.
  - 0: corresponding pin output low-logic level.
  - 1: corresponding pin output high-logic level.

static inline void GPIO_PortSet(GPIO_Type *base, uint32_t mask)
Sets the output level of the multiple GPIO pins to the logic 1.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro

static inline void GPIO_PortClear(GPIO_Type *base, uint32_t mask)
Sets the output level of the multiple GPIO pins to the logic 0.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro

static inline void GPIO_PortToggle(GPIO_Type *base, uint32_t mask)
Reverses the current output logic of the multiple GPIO pins.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro

static inline uint32_t GPIO_PinRead(GPIO_Type *base, uint32_t pin)

Reads the current input value of the GPIO port.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- pin – GPIO pin number

Return values

GPIO – port input value

- 0: corresponding pin input low-logic level.
- 1: corresponding pin input high-logic level.

static inline void GPIO_SetPinInterruptConfig(GPIO_Type *base, uint32_t pin, *gpio_interrupt_config_t* config)

Configures the gpio pin interrupt/DMA request.

Parameters

- base – GPIO peripheral base pointer.
- pin – GPIO pin number.
- config – GPIO pin interrupt configuration.
  - *kGPIO_InterruptStatusFlagDisabled*: Interrupt/DMA request disabled.
  - *kGPIO_DMARisingEdge* : DMA request on rising edge(if the DMA requests exit).
  - *kGPIO_DMAFallingEdge*: DMA request on falling edge(if the DMA requests exit).
  - *kGPIO_DMAEitherEdge* : DMA request on either edge(if the DMA requests exit).
  - *kGPIO_FlagRisingEdge* : Flag sets on rising edge(if the Flag states exit).
  - *kGPIO_FlagFallingEdge* : Flag sets on falling edge(if the Flag states exit).
  - *kGPIO_FlagEitherEdge* : Flag sets on either edge(if the Flag states exit).
  - *kGPIO_InterruptLogicZero* : Interrupt when logic zero.
  - *kGPIO_InterruptRisingEdge* : Interrupt on rising edge.
  - *kGPIO_InterruptFallingEdge*: Interrupt on falling edge.
  - *kGPIO_InterruptEitherEdge* : Interrupt on either edge.
  - *kGPIO_InterruptLogicOne* : Interrupt when logic one.
  - *kGPIO_ActiveHighTriggerOutputEnable* : Enable active high-trigger output (if the trigger states exit).
  - *kGPIO_ActiveLowTriggerOutputEnable* : Enable active low-trigger output (if the trigger states exit).

static inline void GPIO_SetPinInterruptChannel(GPIO_Type *base, uint32_t pin, *gpio_interrupt_selection_t* selection)

Configures the gpio pin interrupt/DMA request/trigger output channel selection.

Parameters

- base – GPIO peripheral base pointer.
- pin – GPIO pin number.
- selection – GPIO pin interrupt output selection.

- *kGPIO_InterruptOutput0*: Interrupt/DMA request/trigger output 0.
- *kGPIO_InterruptOutput1* : Interrupt/DMA request/trigger output 1.

uint32_t GPIO_GpioGetInterruptFlags(GPIO_Type *base)

Read the GPIO interrupt status flags.

Parameters

- base – GPIO peripheral base pointer. (GPIOA, GPIOB, GPIOC, and so on.)

Returns

The current GPIO's interrupt status flag. '1' means the related pin's flag is set, '0' means the related pin's flag not set. For example, the return value 0x00010001 means the pin 0 and 17 have the interrupt pending.

uint32_t GPIO_GpioGetInterruptChannelFlags(GPIO_Type *base, uint32_t channel)

Read the GPIO interrupt status flags based on selected interrupt channel(IRQS).

Parameters

- base – GPIO peripheral base pointer. (GPIOA, GPIOB, GPIOC, and so on.)
- channel – '0' means selete interrupt channel 0, '1' means selete interrupt channel 1.

Returns

The current GPIO's interrupt status flag based on the selected interrupt channel. '1' means the related pin's flag is set, '0' means the related pin's flag not set. For example, the return value 0x00010001 means the pin 0 and 17 have the interrupt pending.

uint8_t GPIO_PinGetInterruptFlag(GPIO_Type *base, uint32_t pin)

Read individual pin's interrupt status flag.

Parameters

- base – GPIO peripheral base pointer. (GPIOA, GPIOB, GPIOC, and so on)
- pin – GPIO specific pin number.

Returns

The current selected pin's interrupt status flag.

void GPIO_GpioClearInterruptFlags(GPIO_Type *base, uint32_t mask)

Clears GPIO pin interrupt status flags.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro

void GPIO_GpioClearInterruptChannelFlags(GPIO_Type *base, uint32_t mask, uint32_t channel)

Clears GPIO pin interrupt status flags based on selected interrupt channel(IRQS).

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro
- channel – '0' means selete interrupt channel 0, '1' means selete interrupt channel 1.

void GPIO_PinClearInterruptFlag(GPIO_Type *base, uint32_t pin)

Clear GPIO individual pin's interrupt status flag.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on).
- pin – GPIO specific pin number.

static inline void GPIO_SetMultipleInterruptPinsConfig(GPIO_Type *base, uint32_t mask, *gpio_interrupt_config_t* config)

Sets the GPIO interrupt configuration in PCR register for multiple pins.

Parameters

- base – GPIO peripheral base pointer.
- mask – GPIO pin number macro.
- config – GPIO pin interrupt configuration.
  - *kGPIO_InterruptStatusFlagDisabled*: Interrupt disabled.
  - *kGPIO_DMARisingEdge* : DMA request on rising edge(if the DMA requests exit).
  - *kGPIO_DMAFallingEdge*: DMA request on falling edge(if the DMA requests exit).
  - *kGPIO_DMAEitherEdge* : DMA request on either edge(if the DMA requests exit).
  - *kGPIO_FlagRisingEdge* : Flag sets on rising edge(if the Flag states exit).
  - *kGPIO_FlagFallingEdge* : Flag sets on falling edge(if the Flag states exit).
  - *kGPIO_FlagEitherEdge* : Flag sets on either edge(if the Flag states exit).
  - *kGPIO_InterruptLogicZero* : Interrupt when logic zero.
  - *kGPIO_InterruptRisingEdge* : Interrupt on rising edge.
  - *kGPIO_InterruptFallingEdge*: Interrupt on falling edge.
  - *kGPIO_InterruptEitherEdge* : Interrupt on either edge.
  - *kGPIO_InterruptLogicOne* : Interrupt when logic one.
  - *kGPIO_ActiveHighTriggerOutputEnable* : Enable active high-trigger output (if the trigger states exit).
  - *kGPIO_ActiveLowTriggerOutputEnable* : Enable active low-trigger output (if the trigger states exit)..

void GPIO_CheckAttributeBytes(GPIO_Type *base, *gpio_checker_attribute_t* attribute)

brief The GPIO module supports a device-specific number of data ports, organized as 32-bit words/8-bit Bytes. Each 32-bit/8-bit data port includes a GACR register, which defines the byte-level attributes required for a successful access to the GPIO programming model. If the GPIO module's GACR register organized as 32-bit words, the attribute controls for the 4 data bytes in the GACR follow a standard little endian data convention.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- attribute – GPIO checker attribute

GPIO_PortGetInterruptFlags(base)

GPIO_PortClearInterruptFlags(base, mask)

2.38 I3C: I3C Driver

FSL_I3C_DRIVER_VERSION
I3C driver version.

I3C status return codes.

Values:

enumerator kStatus_I3C_Busy
The master is already performing a transfer.

enumerator kStatus_I3C_Idle
The slave driver is idle.

enumerator kStatus_I3C_Nak
The slave device sent a NAK in response to an address.

enumerator kStatus_I3C_WriteAbort
The slave device sent a NAK in response to a write.

enumerator kStatus_I3C_Term
The master terminates slave read.

enumerator kStatus_I3C_HdrParityError
Parity error from DDR read.

enumerator kStatus_I3C_CrcError
CRC error from DDR read.

enumerator kStatus_I3C_ReadFifoError
Read from M/SRDATAB register when FIFO empty.

enumerator kStatus_I3C_WriteFifoError
Write to M/SWDATAB register when FIFO full.

enumerator kStatus_I3C_MsgError
Message SDR/DDR mismatch or read/write message in wrong state

enumerator kStatus_I3C_InvalidReq
Invalid use of request.

enumerator kStatus_I3C_Timeout
The module has stalled too long in a frame.

enumerator kStatus_I3C_SlaveCountExceed
The I3C slave count has exceed the definition in I3C_MAX_DEVCNT.

enumerator kStatus_I3C_IBIWon
The I3C slave event IBI or MR or HJ won the arbitration on a header address.

enumerator kStatus_I3C_OverrunError
Slave internal from-bus buffer/FIFO overrun.

enumerator kStatus_I3C_UnderrunError
Slave internal to-bus buffer/FIFO underrun

enumerator kStatus_I3C_UnderrunNak
Slave internal from-bus buffer/FIFO underrun and NACK error

enumerator kStatus_I3C_InvalidStart
Slave invalid start flag

enumerator kStatus_I3C_SdrParityError
SDR parity error

enumerator kStatus_I3C_S0S1Error
S0 or S1 error

enum _i3c_hdr_mode
I3C HDR modes.
Values:

enumerator kI3C_HDRModeNone

enumerator kI3C_HDRModeDDR

enumerator kI3C_HDRModeTSP

enumerator kI3C_HDRModeTSL

typedef enum *_i3c_hdr_mode* i3c_hdr_mode_t
I3C HDR modes.

typedef struct *_i3c_device_info* i3c_device_info_t
I3C device information.

I3C_RETRY_TIMES
Max loops to wait for I3C operation status complete.
This is the maximum number of loops to wait for I3C operation status complete. If set to 0, it will wait indefinitely.

I3C_MAX_DEVCNT

I3C_IBI_BUFF_SIZE

struct _i3c_device_info

#include <fsl_i3c.h> I3C device information.

Public Members

uint8_t dynamicAddr

Device dynamic address.

uint8_t staticAddr

Static address.

uint8_t dcr

Device characteristics register information.

uint8_t bcr

Bus characteristics register information.

uint16_t vendorID

Device vendor ID(manufacture ID).

uint32_t partNumber

Device part number info

uint16_t maxReadLength

Maximum read length.

uint16_t maxWriteLength

Maximum write length.

uint8_t hdrMode

Support hdr mode, could be OR logic in i3c_hdr_mode.

2.39 I3C Common Driver

typedef struct *_i3c_config* i3c_config_t

Structure with settings to initialize the I3C module, could both initialize master and slave functionality.

This structure holds configuration settings for the I3C peripheral. To initialize this structure to reasonable defaults, call the *I3C_GetDefaultConfig()* function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

uint32_t I3C_GetInstance(I3C_Type *base)

Get which instance current I3C is used.

Parameters

- base – The I3C peripheral base address.

void I3C_GetDefaultConfig(*i3c_config_t* *config)

Provides a default configuration for the I3C peripheral, the configuration covers both master functionality and slave functionality.

This function provides the following default configuration for I3C:

```
config->enableMaster                = kI3C_MasterCapable;
config->disableTimeout              = false;
config->hKeep                       = kI3C_MasterHighKeeperNone;
config->enableOpenDrainStop         = true;
config->enableOpenDrainHigh         = true;
config->baudRate_Hz.i2cBaud         = 400000U;
config->baudRate_Hz.i3cPushPullBaud = 12500000U;
config->baudRate_Hz.i3cOpenDrainBaud = 2500000U;
config->masterDynamicAddress        = 0x0AU;
config->slowClock_Hz                = 1000000U;
config->enableSlave                 = true;
config->vendorID                    = 0x11BU;
config->enableRandomPart            = false;
config->partNumber                  = 0;
config->dcr                         = 0;
config->bcr = 0;
config->hdrMode             = (uint8_t)kI3C_HDRModeDDR;
config->nakAllRequest       = false;
config->ignoreS0S1Error     = false;
config->offline             = false;
config->matchSlaveStartStop = false;
```

After calling this function, you can override any settings in order to customize the configuration, prior to initializing the common I3C driver with *I3C_Init()*.

Parameters

- config – **[out]** User provided configuration structure for default values. Refer to *i3c_config_t*.

void I3C_Init(I3C_Type *base, const *i3c_config_t* *config, uint32_t sourceClock_Hz)

Initializes the I3C peripheral. This function enables the peripheral clock and initializes the I3C peripheral as described by the user provided configuration. This will initialize both the master peripheral and slave peripheral so that I3C module could work as pure master, pure slave or secondary master, etc. A software reset is performed prior to configuration.

Parameters

- base – The I3C peripheral base address.
- config – User provided peripheral configuration. Use *I3C_GetDefaultConfig()* to get a set of defaults that you can override.
- sourceClock_Hz – Frequency in Hertz of the I3C functional clock. Used to calculate the baud rate divisors, filter widths, and timeout periods.

struct _i3c_config

#include <fsl_i3c.h> Structure with settings to initialize the I3C module, could both initialize master and slave functionality.

This structure holds configuration settings for the I3C peripheral. To initialize this structure to reasonable defaults, call the *I3C_GetDefaultConfig()* function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

Public Members

i3c_master_enable_t enableMaster
Enable master mode.

bool disableTimeout
Whether to disable timeout to prevent the ERRWARN.

i3c_master_hkeep_t hKeep
High keeper mode setting.

bool enableOpenDrainStop
Whether to emit open-drain speed STOP.

bool enableOpenDrainHigh
Enable Open-Drain High to be 1 PPBAUD count for i3c messages, or 1 ODBAUD.

i3c_baudrate_hz_t baudRate_Hz
Desired baud rate settings.

i3c_start_scl_delay_t startSclDelay
I3C SCL delay after START.

i3c_start_scl_delay_t restartSclDelay
I3C SCL delay after Repeated START.

uint8_t masterDynamicAddress
Main master dynamic address configuration.

uint32_t maxWriteLength
Maximum write length.

uint32_t maxReadLength
Maximum read length.

bool enableSlave
Whether to enable slave.

uint8_t staticAddr
Static address.

uint16_t vendorID
Device vendor ID(manufacture ID).

uint32_t partNumber
Device part number info

uint8_t dcr
Device characteristics register information.

uint8_t bcr

Bus characteristics register information.

uint8_t hdrMode

Support hdr mode, could be OR logic in enumeration:i3c_hdr_mode_t.

bool nakAllRequest

Whether to reply NAK to all requests except broadcast CCC.

bool ignoreS0S1Error

Whether to ignore S0/S1 error in SDR mode.

bool offline

Whether to wait 60 us of bus quiet or HDR request to ensure slave track SDR mode safely.

bool matchSlaveStartStop

Whether to assert start/stop status only the time slave is addressed.

2.40 I3C Master Driver

void I3C_MasterGetDefaultConfig(*i3c_master_config_t* *masterConfig)

Provides a default configuration for the I3C master peripheral.

This function provides the following default configuration for the I3C master peripheral:

```
masterConfig->enableMaster            = kI3C_MasterOn;
masterConfig->disableTimeout          = false;
masterConfig->hKeep                   = kI3C_MasterHighKeeperNone;
masterConfig->enableOpenDrainStop     = true;
masterConfig->enableOpenDrainHigh     = true;
masterConfig->baudRate_Hz             = 100000U;
masterConfig->busType                 = kI3C_TypeI2C;
```

After calling this function, you can override any settings in order to customize the configuration, prior to initializing the master driver with *I3C_MasterInit()*.

Parameters

- masterConfig – **[out]** User provided configuration structure for default values. Refer to *i3c_master_config_t*.

void I3C_MasterInit(I3C_Type *base, const *i3c_master_config_t* *masterConfig, uint32_t sourceClock_Hz)

Initializes the I3C master peripheral.

This function enables the peripheral clock and initializes the I3C master peripheral as described by the user provided configuration. A software reset is performed prior to configuration.

Parameters

- base – The I3C peripheral base address.
- masterConfig – User provided peripheral configuration. Use *I3C_MasterGetDefaultConfig()* to get a set of defaults that you can override.

- sourceClock_Hz – Frequency in Hertz of the I3C functional clock. Used to calculate the baud rate divisors, filter widths, and timeout periods.

void I3C_MasterDeinit(I3C_Type *base)

Deinitializes the I3C master peripheral.

This function disables the I3C master peripheral and gates the clock. It also performs a software reset to restore the peripheral to reset conditions.

Parameters

- base – The I3C peripheral base address.

static inline void I3C_MasterEnable(I3C_Type *base, *i3c_master_enable_t* enable)

Set I3C module master mode.

Parameters

- base – The I3C peripheral base address.
- enable – Enable master mode.

status_t I3C_MasterCheckAndClearError(I3C_Type *base, uint32_t status)

status_t I3C_MasterWaitForCtrlDone(I3C_Type *base, bool waitIdle)

status_t I3C_CheckForBusyBus(I3C_Type *base)

void I3C_SlaveGetDefaultConfig(*i3c_slave_config_t* *slaveConfig)

Provides a default configuration for the I3C slave peripheral.

This function provides the following default configuration for the I3C slave peripheral:

```
slaveConfig->enableslave              = true;
```

After calling this function, you can override any settings in order to customize the configuration, prior to initializing the slave driver with I3C_SlaveInit().

Parameters

- slaveConfig – **[out]** User provided configuration structure for default values. Refer to *i3c_slave_config_t*.

void I3C_SlaveInit(I3C_Type *base, const *i3c_slave_config_t* *slaveConfig, uint32_t slowClock_Hz)

Initializes the I3C slave peripheral.

This function enables the peripheral clock and initializes the I3C slave peripheral as described by the user provided configuration.

Parameters

- base – The I3C peripheral base address.
- slaveConfig – User provided peripheral configuration. Use I3C_SlaveGetDefaultConfig() to get a set of defaults that you can override.
- slowClock_Hz – Frequency in Hertz of the I3C slow clock. Used to calculate the bus match condition values. If FSL_FEATURE_I3C_HAS_NO_SCONFIG_BAMATCH defines as 1, this parameter is useless.

void I3C_SlaveDeinit(I3C_Type *base)

Deinitializes the I3C slave peripheral.

This function disables the I3C slave peripheral and gates the clock.

Parameters

- base – The I3C peripheral base address.

static inline void I3C_SlaveEnable(I3C_Type *base, bool isEnable)

Enable/Disable Slave.

Parameters

- base – The I3C peripheral base address.
- isEnable – Enable or disable.

static inline uint32_t I3C_MasterGetStatusFlags(I3C_Type *base)

Gets the I3C master status flags.

A bit mask with the state of all I3C master status flags is returned. For each flag, the corresponding bit in the return value is set if the flag is asserted.

See also:

_i3c_master_flags

Parameters

- base – The I3C peripheral base address.

Returns

State of the status flags:

- 1: related status flag is set.
- 0: related status flag is not set.

static inline void I3C_MasterClearStatusFlags(I3C_Type *base, uint32_t statusMask)

Clears the I3C master status flag state.

The following status register flags can be cleared:

- *kI3C_MasterSlaveStartFlag*
- *kI3C_MasterControlDoneFlag*
- *kI3C_MasterCompleteFlag*
- *kI3C_MasterArbitrationWonFlag*
- *kI3C_MasterSlave2MasterFlag*

Attempts to clear other flags has no effect.

See also:

_i3c_master_flags.

Parameters

- base – The I3C peripheral base address.
- statusMask – A bitmask of status flags that are to be cleared. The mask is composed of *_i3c_master_flags* enumerators OR'd together. You may pass the result of a previous call to *I3C_MasterGetStatusFlags()*.

static inline uint32_t I3C_MasterGetErrorStatusFlags(I3C_Type *base)

Gets the I3C master error status flags.

A bit mask with the state of all I3C master error status flags is returned. For each flag, the corresponding bit in the return value is set if the flag is asserted.

See also:

_i3c_master_error_flags

Parameters

- base – The I3C peripheral base address.

Returns

State of the error status flags:

- 1: related status flag is set.
- 0: related status flag is not set.

static inline void I3C_MasterClearErrorStatusFlags(I3C_Type *base, uint32_t statusMask)

Clears the I3C master error status flag state.

See also:

_i3c_master_error_flags.

Parameters

- base – The I3C peripheral base address.
- statusMask – A bitmask of error status flags that are to be cleared. The mask is composed of *_i3c_master_error_flags* enumerators OR'd together. You may pass the result of a previous call to *I3C_MasterGetStatusFlags()*.

i3c_master_state_t I3C_MasterGetState(I3C_Type *base)

Gets the I3C master state.

Parameters

- base – The I3C peripheral base address.

Returns

I3C master state.

static inline uint32_t I3C_SlaveGetStatusFlags(I3C_Type *base)

Gets the I3C slave status flags.

A bit mask with the state of all I3C slave status flags is returned. For each flag, the corresponding bit in the return value is set if the flag is asserted.

See also:

_i3c_slave_flags

Parameters

- base – The I3C peripheral base address.

Returns

State of the status flags:

- 1: related status flag is set.
- 0: related status flag is not set.

static inline void I3C_SlaveClearStatusFlags(I3C_Type *base, uint32_t statusMask)

Clears the I3C slave status flag state.

The following status register flags can be cleared:

- *kI3C_SlaveBusStartFlag*
- *kI3C_SlaveMatchedFlag*
- *kI3C_SlaveBusStopFlag*

Attempts to clear other flags has no effect.

See also:

_i3c_slave_flags.

Parameters

- base – The I3C peripheral base address.
- statusMask – A bitmask of status flags that are to be cleared. The mask is composed of *_i3c_slave_flags* enumerators OR'd together. You may pass the result of a previous call to I3C_SlaveGetStatusFlags().

static inline uint32_t I3C_SlaveGetErrorStatusFlags(I3C_Type *base)

Gets the I3C slave error status flags.

A bit mask with the state of all I3C slave error status flags is returned. For each flag, the corresponding bit in the return value is set if the flag is asserted.

See also:

_i3c_slave_error_flags

Parameters

- base – The I3C peripheral base address.

Returns

State of the error status flags:

- 1: related status flag is set.
- 0: related status flag is not set.

static inline void I3C_SlaveClearErrorStatusFlags(I3C_Type *base, uint32_t statusMask)

Clears the I3C slave error status flag state.

See also:

_i3c_slave_error_flags.

Parameters

- base – The I3C peripheral base address.

- statusMask – A bitmask of error status flags that are to be cleared. The mask is composed of *_i3c_slave_error_flags* enumerators OR'd together. You may pass the result of a previous call to I3C_SlaveGetErrorStatusFlags().

i3c_slave_activity_state_t I3C_SlaveGetActivityState(I3C_Type *base)

Gets the I3C slave state.

Parameters

- base – The I3C peripheral base address.

Returns

I3C slave activity state, refer *i3c_slave_activity_state_t*.

status_t I3C_SlaveCheckAndClearError(I3C_Type *base, uint32_t status)

static inline void I3C_MasterEnableInterrupts(I3C_Type *base, uint32_t interruptMask)

Enables the I3C master interrupt requests.

All flags except *kI3C_MasterBetweenFlag* and *kI3C_MasterNackDetectFlag* can be enabled as interrupts.

Parameters

- base – The I3C peripheral base address.
- interruptMask – Bit mask of interrupts to enable. See *_i3c_master_flags* for the set of constants that should be OR'd together to form the bit mask.

static inline void I3C_MasterDisableInterrupts(I3C_Type *base, uint32_t interruptMask)

Disables the I3C master interrupt requests.

All flags except *kI3C_MasterBetweenFlag* and *kI3C_MasterNackDetectFlag* can be enabled as interrupts.

Parameters

- base – The I3C peripheral base address.
- interruptMask – Bit mask of interrupts to disable. See *_i3c_master_flags* for the set of constants that should be OR'd together to form the bit mask.

static inline uint32_t I3C_MasterGetEnabledInterrupts(I3C_Type *base)

Returns the set of currently enabled I3C master interrupt requests.

Parameters

- base – The I3C peripheral base address.

Returns

A bitmask composed of *_i3c_master_flags* enumerators OR'd together to indicate the set of enabled interrupts.

static inline uint32_t I3C_MasterGetPendingInterrupts(I3C_Type *base)

Returns the set of pending I3C master interrupt requests.

Parameters

- base – The I3C peripheral base address.

Returns

A bitmask composed of *_i3c_master_flags* enumerators OR'd together to indicate the set of pending interrupts.

static inline void I3C_SlaveEnableInterrupts(I3C_Type *base, uint32_t interruptMask)

Enables the I3C slave interrupt requests.

Only below flags can be enabled as interrupts.

- *kI3C_SlaveBusStartFlag*
- *kI3C_SlaveMatchedFlag*
- *kI3C_SlaveBusStopFlag*
- *kI3C_SlaveRxReadyFlag*
- *kI3C_SlaveTxReadyFlag*
- *kI3C_SlaveDynamicAddrChangedFlag*
- *kI3C_SlaveReceivedCCCFlag*
- *kI3C_SlaveErrorFlag*
- *kI3C_SlaveHDRCommandMatchFlag*
- *kI3C_SlaveCCCHandledFlag*
- *kI3C_SlaveEventSentFlag*

Parameters

- base – The I3C peripheral base address.
- interruptMask – Bit mask of interrupts to enable. See *_i3c_slave_flags* for the set of constants that should be OR'd together to form the bit mask.

static inline void I3C_SlaveDisableInterrupts(I3C_Type *base, uint32_t interruptMask)

Disables the I3C slave interrupt requests.

Only below flags can be disabled as interrupts.

- *kI3C_SlaveBusStartFlag*
- *kI3C_SlaveMatchedFlag*
- *kI3C_SlaveBusStopFlag*
- *kI3C_SlaveRxReadyFlag*
- *kI3C_SlaveTxReadyFlag*
- *kI3C_SlaveDynamicAddrChangedFlag*
- *kI3C_SlaveReceivedCCCFlag*
- *kI3C_SlaveErrorFlag*
- *kI3C_SlaveHDRCommandMatchFlag*
- *kI3C_SlaveCCCHandledFlag*
- *kI3C_SlaveEventSentFlag*

Parameters

- base – The I3C peripheral base address.
- interruptMask – Bit mask of interrupts to disable. See *_i3c_slave_flags* for the set of constants that should be OR'd together to form the bit mask.

static inline uint32_t I3C_SlaveGetEnabledInterrupts(I3C_Type *base)

Returns the set of currently enabled I3C slave interrupt requests.

Parameters

- base – The I3C peripheral base address.

Returns
A bitmask composed of *_i3c_slave_flags* enumerators OR'd together to indicate the set of enabled interrupts.

static inline uint32_t I3C_SlaveGetPendingInterrupts(I3C_Type *base)

Returns the set of pending I3C slave interrupt requests.

Parameters

- base – The I3C peripheral base address.

Returns
A bitmask composed of *_i3c_slave_flags* enumerators OR'd together to indicate the set of pending interrupts.

static inline void I3C_MasterEnableDMA(I3C_Type *base, bool enableTx, bool enableRx, uint32_t width)

Enables or disables I3C master DMA requests.

Parameters

- base – The I3C peripheral base address.
- enableTx – Enable flag for transmit DMA request. Pass true for enable, false for disable.
- enableRx – Enable flag for receive DMA request. Pass true for enable, false for disable.
- width – DMA read/write unit in bytes.

static inline uint32_t I3C_MasterGetTxFifoAddress(I3C_Type *base, uint32_t width)

Gets I3C master transmit data register address for DMA transfer.

Parameters

- base – The I3C peripheral base address.
- width – DMA read/write unit in bytes.

Returns
The I3C Master Transmit Data Register address.

static inline uint32_t I3C_MasterGetRxFifoAddress(I3C_Type *base, uint32_t width)

Gets I3C master receive data register address for DMA transfer.

Parameters

- base – The I3C peripheral base address.
- width – DMA read/write unit in bytes.

Returns
The I3C Master Receive Data Register address.

static inline void I3C_SlaveEnableDMA(I3C_Type *base, bool enableTx, bool enableRx, uint32_t width)

Enables or disables I3C slave DMA requests.

Parameters

- base – The I3C peripheral base address.
- enableTx – Enable flag for transmit DMA request. Pass true for enable, false for disable.
- enableRx – Enable flag for receive DMA request. Pass true for enable, false for disable.
- width – DMA read/write unit in bytes.

static inline uint32_t I3C_SlaveGetTxFifoAddress(I3C_Type *base, uint32_t width)

Gets I3C slave transmit data register address for DMA transfer.

Parameters

- base – The I3C peripheral base address.
- width – DMA read/write unit in bytes.

Returns

The I3C Slave Transmit Data Register address.

static inline uint32_t I3C_SlaveGetRxFifoAddress(I3C_Type *base, uint32_t width)

Gets I3C slave receive data register address for DMA transfer.

Parameters

- base – The I3C peripheral base address.
- width – DMA read/write unit in bytes.

Returns

The I3C Slave Receive Data Register address.

static inline void I3C_MasterSetWatermarks(I3C_Type *base, *i3c_tx_trigger_level_t* txLvl, *i3c_rx_trigger_level_t* rxLvl, bool flushTx, bool flushRx)

Sets the watermarks for I3C master FIFOs.

Parameters

- base – The I3C peripheral base address.
- txLvl – Transmit FIFO watermark level. The *kI3C_MasterTxReadyFlag* flag is set whenever the number of words in the transmit FIFO reaches *txLvl*.
- rxLvl – Receive FIFO watermark level. The *kI3C_MasterRxReadyFlag* flag is set whenever the number of words in the receive FIFO reaches *rxLvl*.
- flushTx – true if TX FIFO is to be cleared, otherwise TX FIFO remains unchanged.
- flushRx – true if RX FIFO is to be cleared, otherwise RX FIFO remains unchanged.

static inline void I3C_MasterGetFifoCounts(I3C_Type *base, size_t *rxCount, size_t *txCount)

Gets the current number of bytes in the I3C master FIFOs.

Parameters

- base – The I3C peripheral base address.
- txCount – **[out]** Pointer through which the current number of bytes in the transmit FIFO is returned. Pass NULL if this value is not required.
- rxCount – **[out]** Pointer through which the current number of bytes in the receive FIFO is returned. Pass NULL if this value is not required.

static inline void I3C_SlaveSetWatermarks(I3C_Type *base, *i3c_tx_trigger_level_t* txLvl, *i3c_rx_trigger_level_t* rxLvl, bool flushTx, bool flushRx)

Sets the watermarks for I3C slave FIFOs.

Parameters

- base – The I3C peripheral base address.
- txLvl – Transmit FIFO watermark level. The *kI3C_SlaveTxReadyFlag* flag is set whenever the number of words in the transmit FIFO reaches *txLvl*.

- rxLvl – Receive FIFO watermark level. The *kI3C_SlaveRxReadyFlag* flag is set whenever the number of words in the receive FIFO reaches *rxLvl*.
- flushTx – true if TX FIFO is to be cleared, otherwise TX FIFO remains unchanged.
- flushRx – true if RX FIFO is to be cleared, otherwise RX FIFO remains unchanged.

static inline void I3C_SlaveGetFifoCounts(I3C_Type *base, size_t *rxCount, size_t *txCount)

Gets the current number of bytes in the I3C slave FIFOs.

Parameters

- base – The I3C peripheral base address.
- txCount – **[out]** Pointer through which the current number of bytes in the transmit FIFO is returned. Pass NULL if this value is not required.
- rxCount – **[out]** Pointer through which the current number of bytes in the receive FIFO is returned. Pass NULL if this value is not required.

void I3C_MasterSetBaudRate(I3C_Type *base, const *i3c_baudrate_hz_t* *baudRate_Hz, uint32_t sourceClock_Hz)

Sets the I3C bus frequency for master transactions.

The I3C master is automatically disabled and re-enabled as necessary to configure the baud rate. Do not call this function during a transfer, or the transfer is aborted.

Note: On devices affected by I3C errata ERR053429, an SDR read with PPBAUD < 2 can lose the last received byte when the RxFIFO fills before the CPU/DMA services it. For safe SDR reads, request a push-pull baud that yields PPBAUD > 1, or guarantee the CPU/DMA drains the RxFIFO fast enough to avoid a Full event.

Parameters

- base – The I3C peripheral base address.
- baudRate_Hz – Pointer to structure of requested bus frequency in Hertz.
- sourceClock_Hz – I3C functional clock frequency in Hertz.

status_t I3C_MasterGetI2CPresetTiming(*i3c_legacy_i2c_speed_mode_t* speed, *i3c_master_src_clk_t* srcClk, *i3c_timing_t* *timing)

Get prevalidated timing values for supported I2C speed.

Parameters

- speed – **[in]** I2C Speed mode.
- srcClk – **[in]** FCLK source clock.
- timing – **[out]** Prevalidated timing values. Valid when kStatus_Success is returned.

Returns

kStatus_Success A supported preset timing is found. kStatus_Fail The requested timing is not supported.

status_t I3C_MasterCalcTiming(const *i3c_master_baudrate_config_t* *baudRate, uint32_t sourceClock_Hz, *i3c_timing_t* *timing)

Calculate timing from desired baud rates.

Parameters

- baudRate – **[in]** Desired baud rates and bus configuration.
- sourceClock_Hz – **[in]** Master peripheral clock (FCLK) frequency in Hz.
- timing – **[out]** I3C timing register field values. Valid only when kStatus_Success is returned.

Returns

kStatus_Success Target rate is achieved. kStatus_Fail Target rate isn't achieved.

void I3C_MasterSetTiming(I3C_Type *base, const *i3c_timing_t* *timing)

Set I3C timing parameters.

Parameters

- base – I3C peripheral base address.
- timing – Pre-calculated timing values.

static inline bool I3C_MasterGetBusIdleState(I3C_Type *base)

Returns whether the bus is idle.

Requires the master mode to be enabled.

Parameters

- base – The I3C peripheral base address.

Return values

- true – Bus is busy.
- false – Bus is idle.

status_t I3C_MasterStartWithRxSize(I3C_Type *base, *i3c_bus_type_t* type, uint8_t address, *i3c_direction_t* dir, uint8_t rxSize)

Sends a START signal and slave address on the I2C/I3C bus, receive size is also specified in the call.

This function is used to initiate a new master mode transfer. First, the bus state is checked to ensure that another master is not occupying the bus. Then a START signal is transmitted, followed by the 7-bit address specified in the a address parameter. Note that this function does not actually wait until the START and address are successfully sent on the bus before returning.

Parameters

- base – The I3C peripheral base address.
- type – The bus type to use in this transaction.
- address – 7-bit slave device address, in bits [6:0].
- dir – Master transfer direction, either *kI3C_Read* or *kI3C_Write*. This parameter is used to set the R/w bit (bit 0) in the transmitted slave address.
- rxSize – Read terminate size for the followed read transfer, limit to 255 bytes.

Return values

- kStatus_Success – START signal and address were successfully enqueued in the transmit FIFO.
- kStatus_I3C_Busy – Another master is currently utilizing the bus.

status_t I3C_MasterStart(I3C_Type *base, *i3c_bus_type_t* type, uint8_t address, *i3c_direction_t* dir)

Sends a START signal and slave address on the I2C/I3C bus.

This function is used to initiate a new master mode transfer. First, the bus state is checked to ensure that another master is not occupying the bus. Then a START signal is transmitted, followed by the 7-bit address specified in the *address* parameter. Note that this function does not actually wait until the START and address are successfully sent on the bus before returning.

Parameters

- base – The I3C peripheral base address.
- type – The bus type to use in this transaction.
- address – 7-bit slave device address, in bits [6:0].
- dir – Master transfer direction, either *kI3C_Read* or *kI3C_Write*. This parameter is used to set the R/w bit (bit 0) in the transmitted slave address.

Return values

- kStatus_Success – START signal and address were successfully enqueued in the transmit FIFO.
- kStatus_I3C_Busy – Another master is currently utilizing the bus.

status_t I3C_MasterRepeatedStartWithRxSize(I3C_Type *base, *i3c_bus_type_t* type, uint8_t address, *i3c_direction_t* dir, uint8_t rxSize)

Sends a repeated START signal and slave address on the I2C/I3C bus, receive size is also specified in the call.

This function is used to send a Repeated START signal when a transfer is already in progress. Like *I3C_MasterStart()*, it also sends the specified 7-bit address. Call this API also configures the read terminate size for the following read transfer. For example, set the rxSize = 2, the following read transfer will be terminated after two bytes of data received. Write transfer will not be affected by the rxSize configuration.

Note: This function exists primarily to maintain compatible APIs between I3C and I2C drivers, as well as to better document the intent of code that uses these APIs.

Parameters

- base – The I3C peripheral base address.
- type – The bus type to use in this transaction.
- address – 7-bit slave device address, in bits [6:0].
- dir – Master transfer direction, either *kI3C_Read* or *kI3C_Write*. This parameter is used to set the R/w bit (bit 0) in the transmitted slave address.
- rxSize – Read terminate size for the followed read transfer, limit to 255 bytes.

Return values

kStatus_Success – Repeated START signal and address were successfully enqueued in the transmit FIFO.

static inline *status_t* I3C_MasterRepeatedStart(I3C_Type *base, *i3c_bus_type_t* type, uint8_t address, *i3c_direction_t* dir)

Sends a repeated START signal and slave address on the I2C/I3C bus.

This function is used to send a Repeated START signal when a transfer is already in progress. Like *I3C_MasterStart()*, it also sends the specified 7-bit address.

Note: This function exists primarily to maintain compatible APIs between I3C and I2C drivers, as well as to better document the intent of code that uses these APIs.

Parameters

- base – The I3C peripheral base address.
- type – The bus type to use in this transaction.
- address – 7-bit slave device address, in bits [6:0].
- dir – Master transfer direction, either *kI3C_Read* or *kI3C_Write*. This parameter is used to set the R/w bit (bit 0) in the transmitted slave address.

Return values

kStatus_Success – Repeated START signal and address were successfully enqueued in the transmit FIFO.

status_t I3C_MasterSend(I3C_Type *base, const void *txBuff, size_t txSize, uint32_t flags)

Performs a polling send transfer on the I2C/I3C bus.

Sends up to *txSize* number of bytes to the previously addressed slave device. The slave may reply with a NAK to any byte in order to terminate the transfer early. If this happens, this function returns *kStatus_I3C_Nak*.

Parameters

- base – The I3C peripheral base address.
- txBuff – The pointer to the data to be transferred.
- txSize – The length in bytes of the data to be transferred.
- flags – Bit mask of options for the transfer. See enumeration *_i3c_master_transfer_flags* for available options.

Return values

- kStatus_Success – Data was sent successfully.
- kStatus_I3C_Busy – Another master is currently utilizing the bus.
- kStatus_I3C_Timeout – The module has stalled too long in a frame.
- kStatus_I3C_Nak – The slave device sent a NAK in response to an address.
- kStatus_I3C_WriteAbort – The slave device sent a NAK in response to a write.
- kStatus_I3C_MsgError – Message SDR/DDR mismatch or read/write message in wrong state.
- kStatus_I3C_WriteFifoError – Write to M/SWDATAB register when FIFO full.
- kStatus_I3C_InvalidReq – Invalid use of request.

status_t I3C_MasterReceive(I3C_Type *base, void *rxBuff, size_t rxSize, uint32_t flags)

Performs a polling receive transfer on the I2C/I3C bus.

Parameters

- base – The I3C peripheral base address.
- rxBuff – The pointer to the data to be transferred.

- rxSize – The length in bytes of the data to be transferred.
- flags – Bit mask of options for the transfer. See enumeration *_i3c_master_transfer_flags* for available options.

Return values

- kStatus_Success – Data was received successfully.
- kStatus_I3C_Busy – Another master is currently utilizing the bus.
- kStatus_I3C_Timeout – The module has stalled too long in a frame.
- kStatus_I3C_Term – The master terminates slave read.
- kStatus_I3C_HdrParityError – Parity error from DDR read.
- kStatus_I3C_CrcError – CRC error from DDR read.
- kStatus_I3C_MsgError – Message SDR/DDR mismatch or read/write message in wrong state.
- kStatus_I3C_ReadFifoError – Read from M/SRDATAB register when FIFO empty.
- kStatus_I3C_InvalidReq – Invalid use of request.

status_t I3C_MasterStop(I3C_Type *base)

Sends a STOP signal on the I2C/I3C bus.

This function does not return until the STOP signal is seen on the bus, or an error occurs.

Parameters

- base – The I3C peripheral base address.

Return values

- kStatus_Success – The STOP signal was successfully sent on the bus and the transaction terminated.
- kStatus_I3C_Busy – Another master is currently utilizing the bus.
- kStatus_I3C_Timeout – The module has stalled too long in a frame.
- kStatus_I3C_InvalidReq – Invalid use of request.

void I3C_MasterEmitRequest(I3C_Type *base, *i3c_bus_request_t* masterReq)

I3C master emit request.

Parameters

- base – The I3C peripheral base address.
- masterReq – I3C master request of type *i3c_bus_request_t*

static inline void I3C_MasterEmitIBIResponse(I3C_Type *base, *i3c_ibi_response_t* ibiResponse)

I3C master emit request.

Parameters

- base – The I3C peripheral base address.
- ibiResponse – I3C master emit IBI response of type *i3c_ibi_response_t*

void I3C_MasterRegisterIBI(I3C_Type *base, *i3c_register_ibi_addr_t* *ibiRule)

I3C master register IBI rule.

Parameters

- base – The I3C peripheral base address.
- ibiRule – Pointer to ibi rule description of type *i3c_register_ibi_addr_t*

void I3C_MasterGetIBIRules(I3C_Type *base, *i3c_register_ibi_addr_t* *ibiRule)

I3C master get IBI rule.

Parameters

- base – The I3C peripheral base address.
- ibiRule – Pointer to store the read out ibi rule description.

i3c_ibi_type_t I3C_GetIBIType(I3C_Type *base)

I3C master get IBI Type.

Parameters

- base – The I3C peripheral base address.

Return values

i3c_ibi_type_t – Type of *i3c_ibi_type_t*.

static inline uint8_t I3C_GetIBIAddress(I3C_Type *base)

I3C master get IBI Address.

Parameters

- base – The I3C peripheral base address.

Return values

The – 8-bit IBI address.

status_t I3C_MasterProcessDAASpecifiedBaudrate(I3C_Type *base, uint8_t *addressList, uint32_t count, *i3c_master_daa_baudrate_t* *daaBaudRate)

Performs a DAA in the i3c bus with specified temporary baud rate.

Parameters

- base – The I3C peripheral base address.
- addressList – The pointer for address list which is used to do DAA.
- count – The address count in the address list.
- daaBaudRate – The temporary baud rate in DAA process, NULL for using initial setting. The initial setting is set back between the completion of the DAA and the return of this function.

Return values

- kStatus_Success – The transaction was started successfully.
- kStatus_I3C_Busy – Either another master is currently utilizing the bus, or a non-blocking transaction is already in progress.
- kStatus_I3C_SlaveCountExceed – The I3C slave count has exceed the definition in I3C_MAX_DEVCNT.

static inline *status_t* I3C_MasterProcessDAA(I3C_Type *base, uint8_t *addressList, uint32_t count)

Performs a DAA in the i3c bus.

Parameters

- base – The I3C peripheral base address.
- addressList – The pointer for address list which is used to do DAA.
- count – The address count in the address list. The initial setting is set back between the completion of the DAA and the return of this function.

Return values

- kStatus_Success – The transaction was started successfully.
- kStatus_I3C_Busy – Either another master is currently utilizing the bus, or a non-blocking transaction is already in progress.
- kStatus_I3C_SlaveCountExceed – The I3C slave count has exceed the definition in I3C_MAX_DEVCNT.

i3c_device_info_t *I3C_MasterGetDeviceListAfterDAA(I3C_Type *base, uint8_t *count)

Get device information list after DAA process is done.

Parameters

- base – The I3C peripheral base address.
- count – **[out]** The pointer to store the available device count.

Returns

Pointer to the i3c_device_info_t array.

void I3C_MasterClearDeviceCount(I3C_Type *base)

Clear the global device count which represents current devices number on the bus. When user resets all dynamic addresses on the bus, should call this API.

Parameters

- base – The I3C peripheral base address.

status_t I3C_MasterTransferBlocking(I3C_Type *base, *i3c_master_transfer_t* *transfer)

Performs a master polling transfer on the I2C/I3C bus.

Note: The API does not return until the transfer succeeds or fails due to error happens during transfer.

Parameters

- base – The I3C peripheral base address.
- transfer – Pointer to the transfer structure.

Return values

- kStatus_Success – Data was received successfully.
- kStatus_I3C_Busy – Another master is currently utilizing the bus.
- kStatus_I3C_IBIWon – The I3C slave event IBI or MR or HJ won the arbitration on a header address.
- kStatus_I3C_Timeout – The module has stalled too long in a frame.
- kStatus_I3C_Nak – The slave device sent a NAK in response to an address.
- kStatus_I3C_WriteAbort – The slave device sent a NAK in response to a write.
- kStatus_I3C_Term – The master terminates slave read.
- kStatus_I3C_HdrParityError – Parity error from DDR read.
- kStatus_I3C_CrcError – CRC error from DDR read.
- kStatus_I3C_MsgError – Message SDR/DDR mismatch or read/write message in wrong state.
- kStatus_I3C_ReadFifoError – Read from M/SRDATAB register when FIFO empty.

- kStatus_I3C_WriteFifoError – Write to M/SWDATAB register when FIFO full.
- kStatus_I3C_InvalidReq – Invalid use of request.

status_t I3C_SlaveSend(I3C_Type *base, const void *txBuff, size_t txSize)

Performs a polling send transfer on the I3C bus.

Parameters

- base – The I3C peripheral base address.
- txBuff – The pointer to the data to be transferred.
- txSize – The length in bytes of the data to be transferred.

Returns

Error or success status returned by API.

status_t I3C_SlaveReceive(I3C_Type *base, void *rxBuff, size_t rxSize)

Performs a polling receive transfer on the I3C bus.

Parameters

- base – The I3C peripheral base address.
- rxBuff – The pointer to the data to be transferred.
- rxSize – The length in bytes of the data to be transferred.

Returns

Error or success status returned by API.

void I3C_MasterTransferCreateHandle(I3C_Type *base, *i3c_master_handle_t* *handle, const *i3c_master_transfer_callback_t* *callback, void *userData)

Creates a new handle for the I3C master non-blocking APIs.

The creation of a handle is for use with the non-blocking APIs. Once a handle is created, there is not a corresponding destroy handle. If the user wants to terminate a transfer, the *I3C_MasterTransferAbort()* API shall be called.

Note: The function also enables the NVIC IRQ for the input I3C. Need to notice that on some SoCs the I3C IRQ is connected to INTMUX, in this case user needs to enable the associated INTMUX IRQ in application.

Parameters

- base – The I3C peripheral base address.
- handle – **[out]** Pointer to the I3C master driver handle.
- callback – User provided pointer to the asynchronous callback function.
- userData – User provided pointer to the application callback data.

status_t I3C_MasterTransferNonBlocking(I3C_Type *base, *i3c_master_handle_t* *handle, *i3c_master_transfer_t* *transfer)

Performs a non-blocking transaction on the I2C/I3C bus.

Parameters

- base – The I3C peripheral base address.
- handle – Pointer to the I3C master driver handle.
- transfer – The pointer to the transfer descriptor.

Return values

- kStatus_Success – The transaction was started successfully.
- kStatus_I3C_Busy – Either another master is currently utilizing the bus, or a non-blocking transaction is already in progress.

status_t I3C_MasterTransferGetCount(I3C_Type *base, *i3c_master_handle_t* *handle, size_t *count)

Returns number of bytes transferred so far.

Parameters

- base – The I3C peripheral base address.
- handle – Pointer to the I3C master driver handle.
- count – **[out]** Number of bytes transferred so far by the non-blocking transaction.

Return values

- kStatus_Success –
- kStatus_NoTransferInProgress – There is not a non-blocking transaction currently in progress.

void I3C_MasterTransferAbort(I3C_Type *base, *i3c_master_handle_t* *handle)

Terminates a non-blocking I3C master transmission early.

Note: It is not safe to call this function from an IRQ handler that has a higher priority than the I3C peripheral's IRQ priority.

Parameters

- base – The I3C peripheral base address.
- handle – Pointer to the I3C master driver handle.

void I3C_MasterTransferHandleIRQ(I3C_Type *base, void *intHandle)

Reusable routine to handle master interrupts.

Note: This function does not need to be called unless you are reimplementing the non-blocking API's interrupt handler routines to add special functionality.

Parameters

- base – The I3C peripheral base address.
- intHandle – Pointer to the I3C master driver handle.

void I3C_DriverIRQHandler(uint32_t instance)

Common IRQ handler entry for all I3C instances.

This function dispatches the IRQ to the correct instance handler using the instance index.

Parameters

- instance – I3C instance number.

enum _i3c_master_flags

I3C master peripheral flags.

The following status register flags can be cleared:

- *kI3C_MasterSlaveStartFlag*
- *kI3C_MasterControlDoneFlag*
- *kI3C_MasterCompleteFlag*
- *kI3C_MasterArbitrationWonFlag*
- *kI3C_MasterSlave2MasterFlag*

All flags except *kI3C_MasterBetweenFlag* and *kI3C_MasterNackDetectFlag* can be enabled as interrupts.

Note: These enums are meant to be OR'd together to form a bit mask.

Values:

enumerator kI3C_MasterBetweenFlag

Between messages/DAAs flag

enumerator kI3C_MasterNackDetectFlag

NACK detected flag

enumerator kI3C_MasterSlaveStartFlag

Slave request start flag

enumerator kI3C_MasterControlDoneFlag

Master request complete flag

enumerator kI3C_MasterCompleteFlag

Transfer complete flag

enumerator kI3C_MasterRxReadyFlag

Rx data ready in Rx buffer flag

enumerator kI3C_MasterTxReadyFlag

Tx buffer ready for Tx data flag

enumerator kI3C_MasterArbitrationWonFlag

Header address won arbitration flag

enumerator kI3C_MasterErrorFlag

Error occurred flag

enumerator kI3C_MasterSlave2MasterFlag

Switch from slave to master flag

enumerator kI3C_MasterClearFlags

enum _i3c_master_error_flags

I3C master error flags to indicate the causes.

Note: These enums are meant to be OR'd together to form a bit mask.

Values:

enumerator kI3C_MasterErrorNackFlag

Slave NACKed the last address

enumerator kI3C_MasterErrorWriteAbortFlag

Slave NACKed the write data

enumerator kI3C_MasterErrorParityFlag

Parity error from DDR read

enumerator kI3C_MasterErrorCrcFlag

CRC error from DDR read

enumerator kI3C_MasterErrorReadFlag

Read from MRDATAB register when FIFO empty

enumerator kI3C_MasterErrorWriteFlag

Write to MWDATAB register when FIFO full

enumerator kI3C_MasterErrorMsgFlag

Message SDR/DDR mismatch or read/write message in wrong state

enumerator kI3C_MasterErrorInvalidReqFlag

Invalid use of request

enumerator kI3C_MasterErrorTimeoutFlag

The module has stalled too long in a frame

enumerator kI3C_MasterAllErrorFlags

All error flags

enum _i3c_master_state

I3C working master state.

Values:

enumerator kI3C_MasterStateIdle

Bus stopped.

enumerator kI3C_MasterStateSlvReq

Bus stopped but slave holding SDA low.

enumerator kI3C_MasterStateMsgSdr
In SDR Message mode from using MWMSG_SDR.

enumerator kI3C_MasterStateNormAct
In normal active SDR mode.

enumerator kI3C_MasterStateDdr
In DDR Message mode.

enumerator kI3C_MasterStateDaa
In ENTDAA mode.

enumerator kI3C_MasterStateIbiAck
Waiting on IBI ACK/NACK decision.

enumerator kI3C_MasterStateIbiRcv
Receiving IBI.

enum _i3c_master_enable
I3C master enable configuration.
Values:

enumerator kI3C_MasterOff
Master off.

enumerator kI3C_MasterOn
Master on.

enumerator kI3C_MasterCapable
Master capable.

enum _i3c_master_hkeep
I3C high keeper configuration.
Values:

enumerator kI3C_MasterHighKeeperNone
Use PUR to hold SCL high.

enumerator kI3C_MasterHighKeeperWiredIn
Use pin_HK controls.

enumerator kI3C_MasterPassiveSDA
Hi-Z for Bus Free and hold SDA.

enumerator kI3C_MasterPassiveSDASCL
Hi-Z both for Bus Free, and can Hi-Z SDA for hold.

enum _i3c_bus_request

Emits the requested operation when doing in pieces vs. by message.

Values:

enumerator kI3C_RequestNone

No request.

enumerator kI3C_RequestEmitStartAddr

Request to emit start and address on bus.

enumerator kI3C_RequestEmitStop

Request to emit stop on bus.

enumerator kI3C_RequestIbiAckNack

Manual IBI ACK or NACK.

enumerator kI3C_RequestProcessDAA

Process DAA.

enumerator kI3C_RequestForceExit

Request to force exit.

enumerator kI3C_RequestAutoIbi

Hold in stopped state, but Auto-emit START,7E.

enum _i3c_bus_type

Bus type with EmitStartAddr.

Values:

enumerator kI3C_TypeI3CSdr

SDR mode of I3C.

enumerator kI3C_TypeI2C

Standard i2c protocol.

enumerator kI3C_TypeI3CDdr

HDR-DDR mode of I3C.

enum _i3c_ibi_response

IBI response.

Values:

enumerator kI3C_IbiRespAck

ACK with no mandatory byte.

enumerator kI3C_IbiRespNack

NACK.

enumerator kI3C_IbiRespAckMandatory
ACK with mandatory byte.

enumerator kI3C_IbiRespManual
Reserved.

enum _i3c_ibi_type
IBI type.
Values:

enumerator kI3C_IbiNormal
In-band interrupt.

enumerator kI3C_IbiHotJoin
slave hot join.

enumerator kI3C_IbiMasterRequest
slave master ship request.

enum _i3c_ibi_state
IBI state.
Values:

enumerator kI3C_IbiReady
In-band interrupt ready state, ready for user to handle.

enumerator kI3C_IbiDataBuffNeed
In-band interrupt need data buffer for data receive.

enumerator kI3C_IbiAckNackPending
In-band interrupt Ack/Nack pending for decision.

enum _i3c_direction
Direction of master and slave transfers.
Values:

enumerator kI3C_Write
Master transmit.

enumerator kI3C_Read
Master receive.

enum _i3c_tx_trigger_level
Watermark of TX int/dma trigger level.
Values:

enumerator kI3C_TxTriggerOnEmpty
Trigger on empty.

enumerator kI3C_TxTriggerUntilOneQuarterOrLess
Trigger on 1/4 full or less.

enumerator kI3C_TxTriggerUntilOneHalfOrLess
Trigger on 1/2 full or less.

enumerator kI3C_TxTriggerUntilOneLessThanFull
Trigger on 1 less than full or less.

enum _i3c_rx_trigger_level
Watermark of RX int/dma trigger level.
Values:

enumerator kI3C_RxTriggerOnNotEmpty
Trigger on not empty.

enumerator kI3C_RxTriggerUntilOneQuarterOrMore
Trigger on 1/4 full or more.

enumerator kI3C_RxTriggerUntilOneHalfOrMore
Trigger on 1/2 full or more.

enumerator kI3C_RxTriggerUntilThreeQuarterOrMore
Trigger on 3/4 full or more.

enum _i3c_rx_term_ops
I3C master read termination operations.
Values:

enumerator kI3C_RxTermDisable
Master doesn't terminate read, used for CCC transfer.

enumerator kI3C_RxAutoTerm
Master auto terminate read after receiving specified bytes(<=255).

enumerator kI3C_RxTermLastByte
Master terminates read at any time after START, no length limitation.

enum _i3c_start_scl_delay
I3C start SCL delay options.
Values:

enumerator kI3C_NoDelay
No delay.

enumerator kI3C_IncreaseSclHalfPeriod
Increases SCL clock period by 1/2.

enumerator kI3C_IncreaseSclOnePeriod
Increases SCL clock period by 1.

enumerator kI3C_IncreaseSclOneAndHalfPeriod
Increases SCL clock period by 1 1/2

enum _i3c_master_bus_mode
I3C bus topology. Selects how the baud rate is calculated for the bus.
Values:

enumerator kI3C_PureBus
Only I3C devices on the bus.

enumerator kI3C_MixedFastBus
I3C and legacy I2C Fm/Fm+ devices share the bus.

enumerator kI3C_LimitedBus
I3C controller on a legacy I2C bus.

enum _i3c_legacy_i2c_speed_mode
Legacy I2C preset selector.
Values:

enumerator kI3C_LegacyI2CStandardMode
Reserved for future Standard-mode support.

enumerator kI3C_LegacyI2CFastMode
Legacy I2C Fast-mode preset.

enumerator kI3C_LegacyI2CFastModePlus
Legacy I2C Fast-mode Plus preset.

enum _i3c_master_src_clk
Validated source clock selector for I2C timing presets.
Values:

enumerator kI3C_MasterSrcClk24M
Use the validated 24 MHz timing table.

enumerator kI3C_MasterSrcClk25M
Use the validated 25 MHz timing table.

enum _i3c_master_transfer_flags
Transfer option flags.

Note: These enumerations are intended to be OR'd together to form a bit mask of options for the *_i3c_master_transfer::flags* field.

Values:

enumerator kI3C_TransferDefaultFlag
Transfer starts with a start signal, stops with a stop signal.

enumerator kI3C_TransferNoStartFlag
Don't send a start condition, address, and sub address

enumerator kI3C_TransferRepeatedStartFlag
Send a repeated start condition

enumerator kI3C_TransferNoStopFlag
Don't send a stop condition.

enumerator kI3C_TransferWordsFlag
Transfer in words, else transfer in bytes.

enumerator kI3C_TransferDisableRxTermFlag
Disable Rx termination. Note: It's for I3C CCC transfer.

enumerator kI3C_TransferRxAutoTermFlag
Set Rx auto-termination. Note: It's adaptive based on Rx size(<=255 bytes) except in I3C_MasterReceive.

enumerator kI3C_TransferStartWithBroadcastAddr
Start transfer with 0x7E, then read/write data with device address.

typedef enum *_i3c_master_state* i3c_master_state_t
I3C working master state.

typedef enum *_i3c_master_enable* i3c_master_enable_t
I3C master enable configuration.

typedef enum *_i3c_master_hkeep* i3c_master_hkeep_t
I3C high keeper configuration.

typedef enum *_i3c_bus_request* i3c_bus_request_t
Emits the requested operation when doing in pieces vs. by message.

typedef enum *_i3c_bus_type* i3c_bus_type_t
Bus type with EmitStartAddr.

typedef enum *_i3c_ibi_response* i3c_ibi_response_t
IBI response.

typedef enum *_i3c_ibi_type* i3c_ibi_type_t
IBI type.

typedef enum *_i3c_ibi_state* i3c_ibi_state_t
IBI state.

typedef enum *_i3c_direction* i3c_direction_t

Direction of master and slave transfers.

typedef enum *_i3c_tx_trigger_level* i3c_tx_trigger_level_t

Watermark of TX int/dma trigger level.

typedef enum *_i3c_rx_trigger_level* i3c_rx_trigger_level_t

Watermark of RX int/dma trigger level.

typedef enum *_i3c_rx_term_ops* i3c_rx_term_ops_t

I3C master read termination operations.

typedef enum *_i3c_start_scl_delay* i3c_start_scl_delay_t

I3C start SCL delay options.

typedef struct *_i3c_register_ibi_addr* i3c_register_ibi_addr_t

Structure with setting master IBI rules and slave registry.

typedef struct *_i3c_baudrate* i3c_baudrate_hz_t

Structure with I3C baudrate settings.

typedef struct *_i3c_master_daa_baudrate* i3c_master_daa_baudrate_t

I3C DAA baud rate configuration.

typedef enum *_i3c_master_bus_mode* i3c_master_bus_mode_t

I3C bus topology. Selects how the baud rate is calculated for the bus.

typedef enum *_i3c_legacy_i2c_speed_mode* i3c_legacy_i2c_speed_mode_t

Legacy I2C preset selector.

typedef enum *_i3c_master_src_clk* i3c_master_src_clk_t

Validated source clock selector for I2C timing presets.

typedef struct *_i3c_master_baudrate_config* i3c_master_baudrate_config_t

I3C master baud rate configuration.

typedef struct *_i3c_timing* i3c_timing_t

Pre-calculated I3C MCONFIG timing fields.

Pre-compute the timing at init, then switch with *I3C_MasterSetTiming()*. The actualXxxBaud fields report the rates the hardware achieves.

typedef struct *_i3c_master_config* i3c_master_config_t

Structure with settings to initialize the I3C master module.

This structure holds configuration settings for the I3C peripheral. To initialize this structure to reasonable defaults, call the *I3C_MasterGetDefaultConfig()* function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

typedef struct *_i3c_master_transfer* i3c_master_transfer_t

typedef struct *_i3c_master_handle* i3c_master_handle_t

typedef struct *_i3c_master_transfer_callback* i3c_master_transfer_callback_t

i3c master callback functions.

typedef void (*i3c_master_isr_t)(I3C_Type *base, void *handle)

Typedef for master interrupt handler.

struct _i3c_register_ibi_addr

#include <fsl_i3c.h> Structure with setting master IBI rules and slave registry.

Public Members

uint8_t address[5]

Address array for registry.

bool i3cFastStart

Allow the START header to run as push-pull speed if all dynamic addresses take MSB 0.

bool ibiHasPayload

Whether the address array has mandatory IBI byte.

struct _i3c_baudrate

#include <fsl_i3c.h> Structure with I3C baudrate settings.

Public Members

uint32_t i2cBaud

Desired I2C baud rate in Hertz.

uint32_t i3cPushPullBaud

Desired I3C push-pull baud rate in Hertz.

uint32_t i3cOpenDrainBaud

Desired I3C open-drain baud rate in Hertz.

struct _i3c_master_daa_baudrate

#include <fsl_i3c.h> I3C DAA baud rate configuration.

Public Members

uint32_t sourceClock_Hz
: FCLK, function clock in Hertz.

uint32_t i3cPushPullBaud
: Desired I3C push-pull baud rate in Hertz.

uint32_t i3cOpenDrainBaud
: Desired I3C open-drain baud rate in Hertz.

struct _i3c_master_baudrate_config

#include <fsl_i3c.h> I3C master baud rate configuration.

Public Members

i3c_master_bus_mode_t busMode
: Bus topology.

uint32_t i2cBaud
: Desired legacy I2C baud rate in Hz; 0 = do not program I2CBAUD.

uint32_t i3cPushPullBaud
: Desired I3C push-pull SCL frequency in Hz.

uint32_t i3cOpenDrainBaud
: Desired I3C open-drain SCL frequency in Hz.

bool enableODHPP
: Open-drain HIGH shape: true = narrow (normal I3C frames), false = symmetric (required for the first-7Eh broadcast).

struct _i3c_timing

#include <fsl_i3c.h> Pre-calculated I3C MCONFIG timing fields.

Pre-compute the timing at init, then switch with *I3C_MasterSetTiming()*. The actualXxxBaud fields report the rates the hardware achieves.

Public Members

uint8_t ppBaud
: MCONFIG[PPBAUD] field.

uint8_t ppLow
: MCONFIG[PPLOW] field.

uint8_t odBaud
: MCONFIG[ODBAUD] field (0 is forbidden).

bool odHighPP
: MCONFIG[ODHPP] field.

uint8_t i2cBaud
: MCONFIG[I2CBAUD] field.

uint32_t actualPpBaud
: Achieved PP SCL frequency in Hz.

uint32_t actualOdBaud
: Achieved OD SCL frequency in Hz.

uint32_t actualI2cBaud
: Achieved I2C SCL frequency in Hz (0 if no I2C is configured).

struct _i3c_master_config
: *#include <fsl_i3c.h>* Structure with settings to initialize the I3C master module.

  This structure holds configuration settings for the I3C peripheral. To initialize this structure to reasonable defaults, call the *I3C_MasterGetDefaultConfig()* function and pass a pointer to your configuration structure instance.

  The configuration structure can be made constant so it resides in flash.

  Public Members

  i3c_master_enable_t enableMaster
  : Enable master mode.

  bool disableTimeout
  : Whether to disable timeout to prevent the ERRWARN.

  i3c_master_hkeep_t hKeep
  : High keeper mode setting.

  bool enableOpenDrainStop
  : Whether to emit open-drain speed STOP.

  bool enableOpenDrainHigh
  : Enable Open-Drain High to be 1 PPBAUD count for i3c messages, or 1 ODBAUD.

  i3c_baudrate_hz_t baudRate_Hz
  : Desired baud rate settings.

  i3c_start_scl_delay_t startSclDelay
  : I3C SCL delay after START.

  i3c_start_scl_delay_t restartSclDelay
  : I3C SCL delay after Repeated START.

struct __i3c_master_transfer_callback

#include <fsl_i3c.h> i3c master callback functions.

Public Members

void (*slave2Master)(I3C_Type *base, void *userData)

Transfer complete callback

void (*ibiCallback)(I3C_Type *base, *i3c_master_handle_t* *handle, *i3c_ibi_type_t* ibiType, *i3c_ibi_state_t* ibiState)

IBI event callback

void (*transferComplete)(I3C_Type *base, *i3c_master_handle_t* *handle, *status_t* completionStatus, void *userData)

Transfer complete callback

struct __i3c_master_transfer

#include <fsl_i3c.h> Non-blocking transfer descriptor structure.

This structure is used to pass transaction parameters to the *I3C_MasterTransferNonBlocking()* API.

Public Members

uint32_t flags

Bit mask of options for the transfer. See enumeration *_i3c_master_transfer_flags* for available options. Set to 0 or *kI3C_TransferDefaultFlag* for normal transfers.

uint8_t slaveAddress

The 7-bit slave address.

i3c_direction_t direction

Either *kI3C_Read* or *kI3C_Write*.

uint32_t subaddress

Sub address. Transferred MSB first.

size_t subaddressSize

Length of sub address to send in bytes. Maximum size is 4 bytes.

void *data

Pointer to data to transfer.

size_t dataSize

Number of bytes to transfer.

i3c_bus_type_t busType

bus type.

i3c_ibi_response_t ibiResponse
ibi response during transfer.

struct _i3c_master_handle
#include <fsl_i3c.h> Driver handle for master non-blocking APIs.

Note: The contents of this structure are private and subject to change.

Public Members

uint8_t state
Transfer state machine current state.

uint32_t remainingBytes
Remaining byte count in current state.

i3c_rx_term_ops_t rxTermOps
Read termination operation.

i3c_master_transfer_t transfer
Copy of the current transfer info.

uint8_t ibiAddress
Slave address which request IBI.

uint8_t *ibiBuff
Pointer to IBI buffer to keep ibi bytes.

size_t ibiPayloadSize
IBI payload size.

i3c_ibi_type_t ibiType
IBI type.

i3c_master_transfer_callback_t callback
Callback functions pointer.

void *userData
Application data passed to callback.

2.41 I3C Master DMA Driver

void I3C_MasterTransferCreateHandleEDMA(I3C_Type *base, *i3c_master_edma_handle_t* *handle, const *i3c_master_edma_callback_t* *callback, void *userData, *edma_handle_t* *rxDmaHandle, *edma_handle_t* *txDmaHandle)

Create a new handle for the I3C master DMA APIs.

The creation of a handle is for use with the DMA APIs. Once a handle is created, there is not a corresponding destroy handle. If the user wants to terminate a transfer, the I3C_MasterTransferAbortDMA() API shall be called.

For devices where the I3C send and receive DMA requests are OR'd together, the *txDmaHandle* parameter is ignored and may be set to NULL.

Parameters

- base – The I3C peripheral base address.
- handle – Pointer to the I3C master driver handle.
- callback – User provided pointer to the asynchronous callback function.
- userData – User provided pointer to the application callback data.
- rxDmaHandle – Handle for the DMA receive channel. Created by the user prior to calling this function.
- txDmaHandle – Handle for the DMA transmit channel. Created by the user prior to calling this function.

status_t I3C_MasterTransferEDMA(I3C_Type *base, *i3c_master_edma_handle_t* *handle, *i3c_master_transfer_t* *transfer)

Performs a non-blocking DMA-based transaction on the I3C bus.

The callback specified when the *handle* was created is invoked when the transaction has completed.

Note: On parts affected by ERR053412, the I3C controller stalls SCL when the RxFIFO becomes full and does not recover after CPU read FIFO, bus will be stalling indefinitely. This DMA-based API services the RxFIFO with EDMA so it never fills, and is the recommended workaround on affected parts.

Parameters

- base – The I3C peripheral base address.
- handle – Pointer to the I3C master driver handle.
- transfer – The pointer to the transfer descriptor.

Return values

- kStatus_Success – The transaction was started successfully.
- kStatus_I3C_Busy – Either another master is currently utilizing the bus, or another DMA transaction is already in progress.

status_t I3C_MasterTransferGetCountEDMA(I3C_Type *base, *i3c_master_edma_handle_t* *handle, size_t *count)

Returns number of bytes transferred so far.

Parameters

- base – The I3C peripheral base address.
- handle – Pointer to the I3C master driver handle.
- count – **[out]** Number of bytes transferred so far by the non-blocking transaction.

Return values

- kStatus_Success –
- kStatus_NoTransferInProgress – There is not a DMA transaction currently in progress.

void I3C_MasterTransferAbortEDMA(I3C_Type *base, *i3c_master_edma_handle_t* *handle)

Terminates a non-blocking I3C master transmission early.

Note: It is not safe to call this function from an IRQ handler that has a higher priority than the DMA peripheral's IRQ priority.

Parameters

- base – The I3C peripheral base address.
- handle – Pointer to the I3C master driver handle.

void I3C_MasterTransferEDMAHandleIRQ(I3C_Type *base, void *i3cHandle)

Reusable routine to handle master interrupts.

Note: This function does not need to be called unless you are reimplementing the non-blocking API's interrupt handler routines to add special functionality.

Parameters

- base – The I3C peripheral base address.
- i3cHandle – Pointer to the I3C master DMA driver handle.

typedef struct *_i3c_master_edma_handle* i3c_master_edma_handle_t

typedef struct *_i3c_master_edma_callback* i3c_master_edma_callback_t

i3c master callback functions.

struct _i3c_master_edma_callback

#include <fsl_i3c_edma.h> i3c master callback functions.

Public Members

void (*slave2Master)(I3C_Type *base, void *userData)

Target asks for controller request.

void (*ibiCallback)(I3C_Type *base, *i3c_master_edma_handle_t* *handle, *i3c_ibi_type_t* ibiType, *i3c_ibi_state_t* ibiState)

IBI event callback.

void (*transferComplete)(I3C_Type *base, *i3c_master_edma_handle_t* *handle, *status_t* status, void *userData)

Transfer complete callback.

struct __i3c_master_edma_handle

#include <fsl_i3c_edma.h> Driver handle for master EDMA APIs.

Note: The contents of this structure are private and subject to change.

Public Members

I3C_Type *base

I3C base pointer.

uint8_t state

Transfer state machine current state.

uint32_t transferCount

Indicates progress of the transfer

uint8_t subaddressBuffer[4]

Saving subaddress command.

uint8_t subaddressCount

Saving command count.

i3c_master_transfer_t transfer

Copy of the current transfer info.

i3c_master_edma_callback_t callback

Callback function pointer.

void *userData

Application data passed to callback.

edma_handle_t *rxDmaHandle

Handle for receive DMA channel.

edma_handle_t *txDmaHandle

Handle for transmit DMA channel.

bool ibiFlag

IBIWON flag.

uint8_t ibiAddress

Slave address which request IBI.

uint8_t *ibiBuff

Pointer to IBI buffer to keep ibi bytes.

size_t ibiPayloadSize
IBI payload size.

i3c_ibi_type_t ibiType
IBI type.

status_t result
Transfer result.

2.42 I3C Slave Driver

void I3C_SlaveGetDefaultConfig(*i3c_slave_config_t* *slaveConfig)
Provides a default configuration for the I3C slave peripheral.

This function provides the following default configuration for the I3C slave peripheral:

```
slaveConfig->enableslave              = true;
```

After calling this function, you can override any settings in order to customize the configuration, prior to initializing the slave driver with I3C_SlaveInit().

Parameters

- slaveConfig – **[out]** User provided configuration structure for default values. Refer to *i3c_slave_config_t*.

void I3C_SlaveInit(I3C_Type *base, const *i3c_slave_config_t* *slaveConfig, uint32_t slowClock_Hz)
Initializes the I3C slave peripheral.

This function enables the peripheral clock and initializes the I3C slave peripheral as described by the user provided configuration.

Parameters

- base – The I3C peripheral base address.
- slaveConfig – User provided peripheral configuration. Use I3C_SlaveGetDefaultConfig() to get a set of defaults that you can override.
- slowClock_Hz – Frequency in Hertz of the I3C slow clock. Used to calculate the bus match condition values. If FSL_FEATURE_I3C_HAS_NO_SCONFIG_BAMATCH defines as 1, this parameter is useless.

void I3C_SlaveDeinit(I3C_Type *base)
Deinitializes the I3C slave peripheral.

This function disables the I3C slave peripheral and gates the clock.

Parameters

- base – The I3C peripheral base address.

static inline void I3C_SlaveEnable(I3C_Type *base, bool isEnable)
Enable/Disable Slave.

Parameters

- base – The I3C peripheral base address.
- isEnable – Enable or disable.

static inline uint32_t I3C_SlaveGetStatusFlags(I3C_Type *base)

Gets the I3C slave status flags.

A bit mask with the state of all I3C slave status flags is returned. For each flag, the corresponding bit in the return value is set if the flag is asserted.

See also:

_i3c_slave_flags

Parameters

- base – The I3C peripheral base address.

Returns

State of the status flags:

- 1: related status flag is set.
- 0: related status flag is not set.

static inline void I3C_SlaveClearStatusFlags(I3C_Type *base, uint32_t statusMask)

Clears the I3C slave status flag state.

The following status register flags can be cleared:

- *kI3C_SlaveBusStartFlag*
- *kI3C_SlaveMatchedFlag*
- *kI3C_SlaveBusStopFlag*

Attempts to clear other flags has no effect.

See also:

_i3c_slave_flags.

Parameters

- base – The I3C peripheral base address.
- statusMask – A bitmask of status flags that are to be cleared. The mask is composed of *_i3c_slave_flags* enumerators OR'd together. You may pass the result of a previous call to I3C_SlaveGetStatusFlags().

static inline uint32_t I3C_SlaveGetErrorStatusFlags(I3C_Type *base)

Gets the I3C slave error status flags.

A bit mask with the state of all I3C slave error status flags is returned. For each flag, the corresponding bit in the return value is set if the flag is asserted.

See also:

_i3c_slave_error_flags

Parameters

- base – The I3C peripheral base address.

Returns

State of the error status flags:

- 1: related status flag is set.

- 0: related status flag is not set.

static inline void I3C_SlaveClearErrorStatusFlags(I3C_Type *base, uint32_t statusMask)

Clears the I3C slave error status flag state.

See also:

_i3c_slave_error_flags.

Parameters

- base – The I3C peripheral base address.
- statusMask – A bitmask of error status flags that are to be cleared. The mask is composed of *_i3c_slave_error_flags* enumerators OR'd together. You may pass the result of a previous call to I3C_SlaveGetErrorStatusFlags().

i3c_slave_activity_state_t I3C_SlaveGetActivityState(I3C_Type *base)

Gets the I3C slave state.

Parameters

- base – The I3C peripheral base address.

Returns

I3C slave activity state, refer *i3c_slave_activity_state_t*.

static inline void I3C_SlaveEnableInterrupts(I3C_Type *base, uint32_t interruptMask)

Enables the I3C slave interrupt requests.

Only below flags can be enabled as interrupts.

- *kI3C_SlaveBusStartFlag*
- *kI3C_SlaveMatchedFlag*
- *kI3C_SlaveBusStopFlag*
- *kI3C_SlaveRxReadyFlag*
- *kI3C_SlaveTxReadyFlag*
- *kI3C_SlaveDynamicAddrChangedFlag*
- *kI3C_SlaveReceivedCCCFlag*
- *kI3C_SlaveErrorFlag*
- *kI3C_SlaveHDRCommandMatchFlag*
- *kI3C_SlaveCCCHandledFlag*
- *kI3C_SlaveEventSentFlag*

Parameters

- base – The I3C peripheral base address.
- interruptMask – Bit mask of interrupts to enable. See *_i3c_slave_flags* for the set of constants that should be OR'd together to form the bit mask.

static inline void I3C_SlaveDisableInterrupts(I3C_Type *base, uint32_t interruptMask)

Disables the I3C slave interrupt requests.

Only below flags can be disabled as interrupts.

- *kI3C_SlaveBusStartFlag*

- *kI3C_SlaveMatchedFlag*
- *kI3C_SlaveBusStopFlag*
- *kI3C_SlaveRxReadyFlag*
- *kI3C_SlaveTxReadyFlag*
- *kI3C_SlaveDynamicAddrChangedFlag*
- *kI3C_SlaveReceivedCCCFlag*
- *kI3C_SlaveErrorFlag*
- *kI3C_SlaveHDRCommandMatchFlag*
- *kI3C_SlaveCCCHandledFlag*
- *kI3C_SlaveEventSentFlag*

Parameters

- base – The I3C peripheral base address.
- interruptMask – Bit mask of interrupts to disable. See *_i3c_slave_flags* for the set of constants that should be OR'd together to form the bit mask.

static inline uint32_t I3C_SlaveGetEnabledInterrupts(I3C_Type *base)

Returns the set of currently enabled I3C slave interrupt requests.

Parameters

- base – The I3C peripheral base address.

Returns

A bitmask composed of *_i3c_slave_flags* enumerators OR'd together to indicate the set of enabled interrupts.

static inline uint32_t I3C_SlaveGetPendingInterrupts(I3C_Type *base)

Returns the set of pending I3C slave interrupt requests.

Parameters

- base – The I3C peripheral base address.

Returns

A bitmask composed of *_i3c_slave_flags* enumerators OR'd together to indicate the set of pending interrupts.

static inline void I3C_SlaveEnableDMA(I3C_Type *base, bool enableTx, bool enableRx, uint32_t width)

Enables or disables I3C slave DMA requests.

Parameters

- base – The I3C peripheral base address.
- enableTx – Enable flag for transmit DMA request. Pass true for enable, false for disable.
- enableRx – Enable flag for receive DMA request. Pass true for enable, false for disable.
- width – DMA read/write unit in bytes.

static inline uint32_t I3C_SlaveGetTxFifoAddress(I3C_Type *base, uint32_t width)

Gets I3C slave transmit data register address for DMA transfer.

Parameters

- base – The I3C peripheral base address.

- width – DMA read/write unit in bytes.

Returns
The I3C Slave Transmit Data Register address.

static inline uint32_t I3C_SlaveGetRxFifoAddress(I3C_Type *base, uint32_t width)

Gets I3C slave receive data register address for DMA transfer.

Parameters

- base – The I3C peripheral base address.
- width – DMA read/write unit in bytes.

Returns
The I3C Slave Receive Data Register address.

static inline void I3C_SlaveSetWatermarks(I3C_Type *base, *i3c_tx_trigger_level_t* txLvl, *i3c_rx_trigger_level_t* rxLvl, bool flushTx, bool flushRx)

Sets the watermarks for I3C slave FIFOs.

Parameters

- base – The I3C peripheral base address.
- txLvl – Transmit FIFO watermark level. The *kI3C_SlaveTxReadyFlag* flag is set whenever the number of words in the transmit FIFO reaches *txLvl*.
- rxLvl – Receive FIFO watermark level. The *kI3C_SlaveRxReadyFlag* flag is set whenever the number of words in the receive FIFO reaches *rxLvl*.
- flushTx – true if TX FIFO is to be cleared, otherwise TX FIFO remains unchanged.
- flushRx – true if RX FIFO is to be cleared, otherwise RX FIFO remains unchanged.

static inline void I3C_SlaveGetFifoCounts(I3C_Type *base, size_t *rxCount, size_t *txCount)

Gets the current number of bytes in the I3C slave FIFOs.

Parameters

- base – The I3C peripheral base address.
- txCount – **[out]** Pointer through which the current number of bytes in the transmit FIFO is returned. Pass NULL if this value is not required.
- rxCount – **[out]** Pointer through which the current number of bytes in the receive FIFO is returned. Pass NULL if this value is not required.

status_t I3C_SlaveSend(I3C_Type *base, const void *txBuff, size_t txSize)

Performs a polling send transfer on the I3C bus.

Parameters

- base – The I3C peripheral base address.
- txBuff – The pointer to the data to be transferred.
- txSize – The length in bytes of the data to be transferred.

Returns
Error or success status returned by API.

status_t I3C_SlaveReceive(I3C_Type *base, void *rxBuff, size_t rxSize)

Performs a polling receive transfer on the I3C bus.

Parameters

- base – The I3C peripheral base address.
- rxBuff – The pointer to the data to be transferred.
- rxSize – The length in bytes of the data to be transferred.

Returns
Error or success status returned by API.

void I3C_SlaveTransferCreateHandle(I3C_Type *base, *i3c_slave_handle_t* *handle, *i3c_slave_transfer_callback_t* callback, void *userData)

Creates a new handle for the I3C slave non-blocking APIs.

The creation of a handle is for use with the non-blocking APIs. Once a handle is created, there is not a corresponding destroy handle. If the user wants to terminate a transfer, the *I3C_SlaveTransferAbort()* API shall be called.

Note: The function also enables the NVIC IRQ for the input I3C. Need to notice that on some SoCs the I3C IRQ is connected to INTMUX, in this case user needs to enable the associated INTMUX IRQ in application.

Parameters

- base – The I3C peripheral base address.
- handle – **[out]** Pointer to the I3C slave driver handle.
- callback – User provided pointer to the asynchronous callback function.
- userData – User provided pointer to the application callback data.

status_t I3C_SlaveTransferNonBlocking(I3C_Type *base, *i3c_slave_handle_t* *handle, uint32_t eventMask)

Starts accepting slave transfers.

Call this API after calling I2C_SlaveInit() and *I3C_SlaveTransferCreateHandle()* to start processing transactions driven by an I2C master. The slave monitors the I2C bus and pass events to the callback that was passed into the call to *I3C_SlaveTransferCreateHandle()*. The callback is always invoked from the interrupt context.

The set of events received by the callback is customizable. To do so, set the *eventMask* parameter to the OR'd combination of *i3c_slave_transfer_event_t* enumerators for the events you wish to receive. The *kI3C_SlaveTransmitEvent* and *kI3C_SlaveReceiveEvent* events are always enabled and do not need to be included in the mask. Alternatively, you can pass 0 to get a default set of only the transmit and receive events that are always enabled. In addition, the *kI3C_SlaveAllEvents* constant is provided as a convenient way to enable all events.

Parameters

- base – The I3C peripheral base address.
- handle – Pointer to struct: *_i3c_slave_handle* structure which stores the transfer state.
- eventMask – Bit mask formed by OR'ing together *i3c_slave_transfer_event_t* enumerators to specify which events to send to the callback. Other accepted values are 0 to get a default set of only the transmit and receive events, and *kI3C_SlaveAllEvents* to enable all events.

Return values

- kStatus_Success – Slave transfers were successfully started.

- kStatus_I3C_Busy – Slave transfers have already been started on this handle.

status_t I3C_SlaveTransferGetCount(I3C_Type *base, *i3c_slave_handle_t* *handle, size_t *count)

Gets the slave transfer status during a non-blocking transfer.

Parameters

- base – The I3C peripheral base address.
- handle – Pointer to i2c_slave_handle_t structure.
- count – **[out]** Pointer to a value to hold the number of bytes transferred. May be NULL if the count is not required.

Return values

- kStatus_Success –
- kStatus_NoTransferInProgress –

void I3C_SlaveTransferAbort(I3C_Type *base, *i3c_slave_handle_t* *handle)

Aborts the slave non-blocking transfers.

Note: This API could be called at any time to stop slave for handling the bus events.

Parameters

- base – The I3C peripheral base address.
- handle – Pointer to struct: *_i3c_slave_handle* structure which stores the transfer state.

void I3C_SlaveTransferHandleIRQ(I3C_Type *base, void *intHandle)

Reusable routine to handle slave interrupts.

Note: This function does not need to be called unless you are reimplementing the non blocking API's interrupt handler routines to add special functionality.

Parameters

- base – The I3C peripheral base address.
- intHandle – Pointer to struct: *_i3c_slave_handle* structure which stores the transfer state.

enum _i3c_slave_flags

I3C slave peripheral flags.

The following status register flags can be cleared:

- *kI3C_SlaveBusStartFlag*
- *kI3C_SlaveMatchedFlag*
- *kI3C_SlaveBusStopFlag*

Only below flags can be enabled as interrupts.

- *kI3C_SlaveBusStartFlag*
- *kI3C_SlaveMatchedFlag*
- *kI3C_SlaveBusStopFlag*

- *kI3C_SlaveRxReadyFlag*
- *kI3C_SlaveTxReadyFlag*
- *kI3C_SlaveDynamicAddrChangedFlag*
- *kI3C_SlaveReceivedCCCFlag*
- *kI3C_SlaveErrorFlag*
- *kI3C_SlaveHDRCommandMatchFlag*
- *kI3C_SlaveCCCHandledFlag*
- *kI3C_SlaveEventSentFlag*

Note: These enums are meant to be OR'd together to form a bit mask.

Values:

enumerator kI3C_SlaveNotStopFlag
Slave status not stop flag

enumerator kI3C_SlaveMessageFlag
Slave status message, indicating slave is listening to the bus traffic or responding

enumerator kI3C_SlaveRequiredReadFlag
Slave status required, either is master doing SDR read from slave, or is IBI pushing out.

enumerator kI3C_SlaveRequiredWriteFlag
Slave status request write, master is doing SDR write to slave, except slave in ENTDAA mode

enumerator kI3C_SlaveBusDAAFlag
I3C bus is in ENTDAA mode

enumerator kI3C_SlaveBusHDRModeFlag
I3C bus is in HDR mode

enumerator kI3C_SlaveBusStartFlag
Start/Re-start event is seen since the bus was last cleared

enumerator kI3C_SlaveMatchedFlag
Slave address(dynamic/static) matched since last cleared

enumerator kI3C_SlaveBusStopFlag
Stop event is seen since the bus was last cleared

enumerator kI3C_SlaveRxReadyFlag
Rx data ready in rx buffer flag

enumerator kI3C_SlaveTxReadyFlag
Tx buffer ready for Tx data flag

enumerator kI3C_SlaveDynamicAddrChangedFlag
Slave dynamic address has been assigned, re-assigned, or lost

enumerator kI3C_SlaveReceivedCCCFlag
Slave received Common command code

enumerator kI3C_SlaveErrorFlag
Error occurred flag

enumerator kI3C_SlaveHDRCommandMatchFlag
High data rate command match

enumerator kI3C_SlaveCCCHandledFlag
Slave received Common command code is handled by I3C module

enumerator kI3C_SlaveEventSentFlag
Slave IBI/P2P/MR/HJ event has been sent

enumerator kI3C_SlaveIbiDisableFlag
Slave in band interrupt is disabled.

enumerator kI3C_SlaveMasterRequestDisabledFlag
Slave master request is disabled.

enumerator kI3C_SlaveHotJoinDisabledFlag
Slave Hot-Join is disabled.

enumerator kI3C_SlaveClearFlags
All flags which are cleared by the driver upon starting a transfer.

enumerator kI3C_SlaveAllIrqFlags

enum _i3c_slave_error_flags
I3C slave error flags to indicate the causes.

Note: These enums are meant to be OR'd together to form a bit mask.

Values:

enumerator kI3C_SlaveErrorOverrunFlag
Slave internal from-bus buffer/FIFO overrun.

enumerator kI3C_SlaveErrorUnderrunFlag
Slave internal to-bus buffer/FIFO underrun

enumerator kI3C_SlaveErrorUnderrunNakFlag
Slave internal from-bus buffer/FIFO underrun and NACK error

enumerator kI3C_SlaveErrorTermFlag
Terminate error from master

enumerator kI3C_SlaveErrorInvalidStartFlag
Slave invalid start flag

enumerator kI3C_SlaveErrorSdrParityFlag
SDR parity error

enumerator kI3C_SlaveErrorHdrParityFlag
HDR parity error

enumerator kI3C_SlaveErrorHdrCRCFlag
HDR-DDR CRC error

enumerator kI3C_SlaveErrorS0S1Flag
S0 or S1 error

enumerator kI3C_SlaveErrorOverreadFlag
Over-read error

enumerator kI3C_SlaveErrorOverwriteFlag
Over-write error

enum __i3c_slave_event
I3C slave.event.
Values:

enumerator kI3C_SlaveEventNormal
Normal mode.

enumerator kI3C_SlaveEventIBI
In band interrupt event.

enumerator kI3C_SlaveEventMasterReq
Master request event.

enumerator kI3C_SlaveEventHotJoinReq
Hot-join event.

enum __i3c_slave_activity_state
I3C slave.activity state.
Values:

enumerator kI3C_SlaveNoLatency
Normal bus operation

enumerator kI3C_SlaveLatency1Ms

1ms of latency.

enumerator kI3C_SlaveLatency100Ms

100ms of latency.

enumerator kI3C_SlaveLatency10S

10s latency.

enum _i3c_slave_transfer_event

Set of events sent to the callback for non blocking slave transfers.

These event enumerations are used for two related purposes. First, a bit mask created by OR'ing together events is passed to *I3C_SlaveTransferNonBlocking()* in order to specify which events to enable. Then, when the slave callback is invoked, it is passed the current event through its *transfer* parameter.

Note: These enumerations are meant to be OR'd together to form a bit mask of events.

Values:

enumerator kI3C_SlaveAddressMatchEvent

Received the slave address after a start or repeated start.

enumerator kI3C_SlaveTransmitEvent

Callback is requested to provide data to transmit (slave-transmitter role).

enumerator kI3C_SlaveReceiveEvent

Callback is requested to provide a buffer in which to place received data (slave-receiver role).

enumerator kI3C_SlaveRequiredTransmitEvent

Callback is requested to provide a buffer in which to place received data (slave-receiver role).

enumerator kI3C_SlaveStartEvent

A start/repeated start was detected.

enumerator kI3C_SlaveHDRCommandMatchEvent

Slave Match HDR Command.

enumerator kI3C_SlaveCompletionEvent

A stop was detected, completing the transfer.

enumerator kI3C_SlaveRequestSentEvent

Slave request event sent.

enumerator kI3C_SlaveReceivedCCCEvent

Slave received CCC event, need to handle by application.

enumerator kI3C_SlaveAllEvents

Bit mask of all available events.

typedef enum *_i3c_slave_event* i3c_slave_event_t

I3C slave.event.

typedef enum *_i3c_slave_activity_state* i3c_slave_activity_state_t

I3C slave.activity state.

typedef struct *_i3c_slave_config* i3c_slave_config_t

Structure with settings to initialize the I3C slave module.

This structure holds configuration settings for the I3C peripheral. To initialize this structure to reasonable defaults, call the I3C_SlaveGetDefaultConfig() function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

typedef enum *_i3c_slave_transfer_event* i3c_slave_transfer_event_t

Set of events sent to the callback for non blocking slave transfers.

These event enumerations are used for two related purposes. First, a bit mask created by OR'ing together events is passed to *I3C_SlaveTransferNonBlocking()* in order to specify which events to enable. Then, when the slave callback is invoked, it is passed the current event through its *transfer* parameter.

Note: These enumerations are meant to be OR'd together to form a bit mask of events.

typedef struct *_i3c_slave_transfer* i3c_slave_transfer_t

I3C slave transfer structure.

typedef struct *_i3c_slave_handle* i3c_slave_handle_t

typedef void (*i3c_slave_transfer_callback_t)(I3C_Type *base, *i3c_slave_transfer_t* *transfer, void *userData)

Slave event callback function pointer type.

This callback is used only for the slave non-blocking transfer API. To install a callback, use the I3C_SlaveSetCallback() function after you have created a handle.

Param base
Base address for the I3C instance on which the event occurred.

Param transfer
Pointer to transfer descriptor containing values passed to and/or from the callback.

Param userData
Arbitrary pointer-sized value passed from the application.

typedef void (*i3c_slave_isr_t)(I3C_Type *base, void *handle)

Typedef for slave interrupt handler.

struct __i3c_slave_config

#include <fsl_i3c.h> Structure with settings to initialize the I3C slave module.

This structure holds configuration settings for the I3C peripheral. To initialize this structure to reasonable defaults, call the I3C_SlaveGetDefaultConfig() function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

Public Members

bool enableSlave

Whether to enable slave.

uint8_t staticAddr

Static address.

uint16_t vendorID

Device vendor ID(manufacture ID).

uint32_t partNumber

Device part number info

uint8_t dcr

Device characteristics register information.

uint8_t bcr

Bus characteristics register information.

uint8_t hdrMode

Support hdr mode, could be OR logic in enumeration:i3c_hdr_mode_t.

bool nakAllRequest

Whether to reply NAK to all requests except broadcast CCC.

bool ignoreS0S1Error

Whether to ignore S0/S1 error in SDR mode.

bool offline

Whether to wait 60 us of bus quiet or HDR request to ensure slave track SDR mode safely.

bool matchSlaveStartStop

Whether to assert start/stop status only the time slave is addressed.

uint32_t maxWriteLength

Maximum write length.

uint32_t maxReadLength

Maximum read length.

struct __i3c_slave_transfer

#include <fsl_i3c.h> I3C slave transfer structure.

Public Members

uint32_t event

Reason the callback is being invoked.

uint8_t *txData

Transfer buffer

size_t txDataSize

Transfer size

uint8_t *rxData

Transfer buffer

size_t rxDataSize

Transfer size

status_t completionStatus

Success or error code describing how the transfer completed. Only applies for *kI3C_SlaveCompletionEvent*.

size_t transferredCount

Number of bytes actually transferred since start or last repeated start.

struct __i3c_slave_handle

#include <fsl_i3c.h> I3C slave handle structure.

Note: The contents of this structure are private and subject to change.

Public Members

i3c_slave_transfer_t transfer

I3C slave transfer copy.

bool isBusy

Whether transfer is busy.

bool wasTransmit

Whether the last transfer was a transmit.

uint32_t eventMask

Mask of enabled events.

uint32_t transferredCount

Count of bytes transferred.

i3c_slave_transfer_callback_t callback

Callback function called at transfer event.

void *userData

Callback parameter passed to callback.

size_t txFifoSize

Tx Fifo size

2.43 I3C Slave DMA Driver

void I3C_SlaveTransferCreateHandleEDMA(I3C_Type *base, *i3c_slave_edma_handle_t* *handle, *i3c_slave_edma_callback_t* callback, void *userData, *edma_handle_t* *rxDmaHandle, *edma_handle_t* *txDmaHandle)

Create a new handle for the I3C slave DMA APIs.

The creation of a handle is for use with the DMA APIs. Once a handle is created, there is not a corresponding destroy handle. If the user wants to terminate a transfer, the I3C_SlaveTransferAbortDMA() API shall be called.

For devices where the I3C send and receive DMA requests are OR'd together, the *txDmaHandle* parameter is ignored and may be set to NULL.

Parameters

- base – The I3C peripheral base address.
- handle – Pointer to the I3C slave driver handle.
- callback – User provided pointer to the asynchronous callback function.
- userData – User provided pointer to the application callback data.
- rxDmaHandle – Handle for the DMA receive channel. Created by the user prior to calling this function.
- txDmaHandle – Handle for the DMA transmit channel. Created by the user prior to calling this function.

status_t I3C_SlaveTransferEDMA(I3C_Type *base, *i3c_slave_edma_handle_t* *handle, *i3c_slave_edma_transfer_t* *transfer, uint32_t eventMask)

Prepares for a non-blocking DMA-based transaction on the I3C bus.

The API will do DMA configuration according to the input transfer descriptor, and the data will be transferred when there's bus master requesting transfer from/to this slave. So the timing of call to this API need be aligned with master application to ensure the transfer is executed as expected. Callback specified when the *handle* was created is invoked when the transaction has completed.

Parameters

- base – The I3C peripheral base address.
- handle – Pointer to the I3C slave driver handle.
- transfer – The pointer to the transfer descriptor.

- eventMask – Bit mask formed by OR'ing together *i3c_slave_transfer_event_t* enumerators to specify which events to send to the callback. The transmit and receive events is not allowed to be enabled.

Return values

- kStatus_Success – The transaction was started successfully.
- kStatus_I3C_Busy – Either another master is currently utilizing the bus, or another DMA transaction is already in progress.
- kStatus_Fail – The transaction can't be set.

void I3C_SlaveTransferAbortEDMA(I3C_Type *base, *i3c_slave_edma_handle_t* *handle)

Abort a slave edma non-blocking transfer in a early time.

Parameters

- base – I3C peripheral base address
- handle – pointer to i3c_slave_edma_handle_t structure

void I3C_SlaveTransferEDMAHandleIRQ(I3C_Type *base, void *i3cHandle)

Reusable routine to handle slave interrupts.

Note: This function does not need to be called unless you are reimplementing the non-blocking API's interrupt handler routines to add special functionality.

Parameters

- base – The I3C peripheral base address.
- i3cHandle – Pointer to the I3C slave DMA driver handle.

typedef struct *_i3c_slave_edma_handle* i3c_slave_edma_handle_t

typedef struct *_i3c_slave_edma_transfer* i3c_slave_edma_transfer_t

I3C slave transfer structure.

typedef void (*i3c_slave_edma_callback_t)(I3C_Type *base, *i3c_slave_edma_transfer_t* *transfer, void *userData)

Slave event callback function pointer type.

This callback is used only for the slave DMA transfer API.

Param base
Base address for the I3C instance on which the event occurred.

Param handle
Pointer to slave DMA transfer handle.

Param transfer
Pointer to transfer descriptor containing values passed to and/or from the callback.

Param userData
Arbitrary pointer-sized value passed from the application.

struct _i3c_slave_edma_transfer

#include <fsl_i3c_edma.h> I3C slave transfer structure.

Public Members

uint32_t event
Reason the callback is being invoked.

uint8_t *txData
Transfer buffer

size_t txDataSize
Transfer size

uint8_t *rxData
Transfer buffer

size_t rxDataSize
Transfer size

status_t completionStatus
Success or error code describing how the transfer completed. Only applies for *kI3C_SlaveCompletionEvent*.

struct __i3c_slave_edma_handle
#include <fsl_i3c_edma.h> I3C slave edma handle structure.

Note: The contents of this structure are private and subject to change.

Public Members

I3C_Type *base
I3C base pointer.

i3c_slave_edma_transfer_t transfer
I3C slave transfer copy.

bool isBusy
Whether transfer is busy.

bool wasTransmit
Whether the last transfer was a transmit.

bool isDdrMode
Whether this is HDR-DDR transfer.

uint32_t eventMask
Mask of enabled events.

i3c_slave_edma_callback_t callback
: Callback function called at transfer event.

edma_handle_t *rxDmaHandle
: Handle for receive DMA channel.

edma_handle_t *txDmaHandle
: Handle for transmit DMA channel.

void *userData
: Callback parameter passed to callback.

2.44 INPUTMUX: Input Multiplexing Driver

FSL_INPUTMUX_DRIVER_VERSION
: Group interrupt driver version for SDK.

void INPUTMUX_Init(void *base)
: Initialize INPUTMUX peripheral.

  This function enables the INPUTMUX clock.

  Parameters

  - base – Base address of the INPUTMUX peripheral.

void INPUTMUX_AttachSignal(void *base, uint16_t index, inputmux_connection_t connection)
: Attaches a signal.

  This function writes a source signal selection into an INPUTMUX multiplexer register. The target register address is computed as:

```
target address = base + pmux_id + index * 4
```

  Each inputmux_connection_t enum value encodes two fields via PMUX_SHIFT (20):

```
31          20 19                    0
+------------+-----------------------+
|  pmux_id   |      output_id        |
+------------+-----------------------+
     |                 |
group base          signal value
addr offset         to write
```

  When N consecutive registers all accept the same set of source signals (same pmux_id), only one set of enum values is defined for the whole group; index (0 ~ N-1) selects which register to write, avoiding duplicate enum entries.

  Example: SCT0 has 8 input mux registers sharing SCT0_INMUX0 = 0x000 as the group base:

```
base
 |
 +--[+0x000] SCT0_INMUX0  <-- index=0
 +--[+0x004] SCT0_INMUX1  <-- index=1
 +--[+0x008] SCT0_INMUX2  <-- index=2
 :   ...
 +--[+0x014] SCT0_INMUX5  <-- index=5  (write target for the call below)
```

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```
:   ...
+--[+0x01C] SCT0_INMUX7  <-- index=7
```

To connect CMP0 output to SCT0 input 5:

```
INPUTMUX_AttachSignal(INPUTMUX, 5, kINPUTMUX_Cmp0OutToSct0);
// write address = base + 0x000 + 5*4 = base + 0x014  (SCT0_INMUX5)
```

For peripherals with only a single register per function (e.g. FREQMEAS_REF_REG = 0x180, FREQMEAS_TAR_REG = 0x184), each register has its own unique pmux_id and index must be 0. The two registers are distinguished by their different pmux_id values, not by index:

```
base
 |
 +--[+0x180] FREQMEAS_REF_REG  (pmux_id=0x180, index=0)
 +--[+0x184] FREQMEAS_TAR_REG  (pmux_id=0x184, index=0)
```

Parameters

- base – Base address of the INPUTMUX peripheral.
- index – Zero-based index of the destination register within its group. Each increment advances the address by 4 bytes. Use 0 for single-register groups.
- connection – Encodes the group base offset (bits [31:PMUX_SHIFT]) and the source signal value (bits [PMUX_SHIFT-1:0]).

void INPUTMUX_Deinit(void *base)

Deinitialize INPUTMUX peripheral.

This function disables the INPUTMUX clock.

Parameters

- base – Base address of the INPUTMUX peripheral.

2.45 Common Driver

FSL_COMMON_DRIVER_VERSION

common driver version.

DEBUG_CONSOLE_DEVICE_TYPE_NONE

No debug console.

DEBUG_CONSOLE_DEVICE_TYPE_UART

Debug console based on UART.

DEBUG_CONSOLE_DEVICE_TYPE_LPUART

Debug console based on LPUART.

DEBUG_CONSOLE_DEVICE_TYPE_LPSCI

Debug console based on LPSCI.

DEBUG_CONSOLE_DEVICE_TYPE_USBCDC
: Debug console based on USBCDC.

DEBUG_CONSOLE_DEVICE_TYPE_FLEXCOMM
: Debug console based on FLEXCOMM.

DEBUG_CONSOLE_DEVICE_TYPE_IUART
: Debug console based on i.MX UART.

DEBUG_CONSOLE_DEVICE_TYPE_VUSART
: Debug console based on LPC_VUSART.

DEBUG_CONSOLE_DEVICE_TYPE_MINI_USART
: Debug console based on LPC_USART.

DEBUG_CONSOLE_DEVICE_TYPE_SWO
: Debug console based on SWO.

DEBUG_CONSOLE_DEVICE_TYPE_QSCI
: Debug console based on QSCI.

MIN(a, b)
: Computes the minimum of *a* and *b*.

MAX(a, b)
: Computes the maximum of *a* and *b*.

UINT16_MAX
: Max value of uint16_t type.

UINT32_MAX
: Max value of uint32_t type.

UINTPTR_SIZE

UINT64_H(X)
: Macro to get upper 32 bits of a 64-bit value

UINT64_L(X)
: Macro to get lower 32 bits of a 64-bit value

MCUX_MASK_INVERT_8(mask)
: 8-bit mask inversion.

MCUX_MASK_INVERT_16(mask)
: 16-bit mask inversion.

MCUX_MASK_INVERT_32(mask)
: 32-bit mask inversion for completeness.

MCUX_REG_WRITE8(reg, value)
: 8-bit register write macro

MCUX_REG_WRITE16(reg, value)
: 16-bit register write macro

MCUX_REG_WRITE32(reg, value)
: 32-bit register write macro

MCUX_REG_READ8(reg)
: 8-bit register read macro

MCUX_REG_READ16(reg)
: 16-bit register read macro

MCUX_REG_READ32(reg)
: 32-bit register read macro

MCUX_REG_BIT_SET8(reg, mask)
: 8-bit register bit set macro

MCUX_REG_BIT_SET16(reg, mask)
: 16-bit register bit set macro

MCUX_REG_BIT_SET32(reg, mask)
: 32-bit register bit set macro

MCUX_REG_BIT_CLEAR8(reg, mask)
: 8-bit register bit clear macro

MCUX_REG_BIT_CLEAR16(reg, mask)
: 16-bit register bit clear macro

MCUX_REG_BIT_CLEAR32(reg, mask)
: 32-bit register bit clear macro

MCUX_REG_BIT_GET8(reg, mask)
: 8-bit register bit get macro

MCUX_REG_BIT_GET16(reg, mask)
: 16-bit register bit get macro

MCUX_REG_BIT_GET32(reg, mask)
: 32-bit register bit get macro

MCUX_REG_MODIFY8(reg, mask, value)
: 32-bit register read-modify-write macro

MCUX_REG_MODIFY16(reg, mask, value)
: 16-bit register read-modify-write macro

MCUX_REG_MODIFY32(reg, mask, value)
: 32-bit register read-modify-write macro

SDK_ATOMIC_LOCAL_ADD(addr, val)
: Add value *val* from the variable at address *address*.

SDK_ATOMIC_LOCAL_SUB(addr, val)
: Subtract value *val* to the variable at address *address*.

SDK_ATOMIC_LOCAL_SET(addr, bits)
: Set the bits specifiled by *bits* to the variable at address *address*.

SDK_ATOMIC_LOCAL_CLEAR(addr, bits)
: Clear the bits specifiled by *bits* to the variable at address *address*.

SDK_ATOMIC_LOCAL_TOGGLE(addr, bits)

Toggle the bits specifiled by *bits* to the variable at address *address*.

SDK_ATOMIC_LOCAL_CLEAR_AND_SET(addr, clearBits, setBits)

For the variable at address *address*, clear the bits specifiled by *clearBits* and set the bits specifiled by *setBits*.

SDK_ATOMIC_LOCAL_COMPARE_AND_SET(addr, expected, newValue)

For the variable at address *address*, check whether the value equal to *expected*. If value same as *expected* then update *newValue* to address and return **true** , else return **false** .

SDK_ATOMIC_LOCAL_TEST_AND_SET(addr, newValue)

For the variable at address *address*, set as *newValue* value and return old value.

USEC_TO_COUNT(us, clockFreqInHz)

Macro to convert a microsecond period to raw count value

COUNT_TO_USEC(count, clockFreqInHz)

Macro to convert a raw count value to microsecond

MSEC_TO_COUNT(ms, clockFreqInHz)

Macro to convert a millisecond period to raw count value

COUNT_TO_MSEC(count, clockFreqInHz)

Macro to convert a raw count value to millisecond

SDK_ISR_EXIT_BARRIER

SDK_ALIGN(var, alignbytes)

Macro to define a variable with alignbytes alignment

SDK_SIZEALIGN(var, alignbytes)

Macro to define a variable with L1 d-cache line size alignment

Macro to define a variable with L2 cache line size alignment

Macro to change a value to a given size aligned value (rounded up)

SDK_SIZEALIGN_UP(var, alignbytes)

Macro to change a value to a given size aligned value (rounded up), the wrapper of SDK_SIZEALIGN

SDK_SIZEALIGN_DOWN(var, alignbytes)

Macro to change a value to a given size aligned value (rounded down)

SDK_IS_ALIGNED(var, alignbytes)

Macro to check if a value is aligned to a given size

AT_NONCACHEABLE_SECTION(var)

Define a variable *var*, and place it in non-cacheable section.

AT_NONCACHEABLE_SECTION_ALIGN(var, alignbytes)

Define a variable *var*, and place it in non-cacheable section, the start address of the variable is aligned to *alignbytes*.

AT_NONCACHEABLE_SECTION_INIT(var)

Define a variable *var* with initial value, and place it in non-cacheable section.

AT_NONCACHEABLE_SECTION_ALIGN_INIT(var, alignbytes)

Define a variable *var* with initial value, and place it in non-cacheable section, the start address of the variable is aligned to *alignbytes*.

AT_CACHE_LINE_SECTION(var)

Define a variable *var*, which is cache line size aligned and be placed in CacheLineData section.

AT_CACHE_LINE_SECTION_INIT(var)

Define a variable *var* with initial value, which is cache line size aligned and be placed in CacheLineData.init section.

AT_QUICKACCESS_SECTION_CODE(func)

Place function in a section which can be accessed quickly by core.

AT_QUICKACCESS_SECTION_DATA(var)

Place data in a section which can be accessed quickly by core.

AT_QUICKACCESS_SECTION_DATA_ALIGN(var, alignbytes)

Place data in a section which can be accessed quickly by core, and the variable address is set to align with *alignbytes*.

MCUX_RAMFUNC

Function attribute to place function in RAM. For example, to place function my_func in ram, use like:

```
MCUX_RAMFUNC my_func
```

RAMFUNCTION_SECTION_CODE(func)

Place function in ram.

MCUX_DEPRECATED

Deprecated APIs.

MCUX_DEPRECATED_MACRO

Deprecated macros.

MCUX_EXPERIMENTAL

Experimental APIs.

MCUX_EXPERIMENTAL_MACRO

Experimental macros.

enum _status_groups

Status group numbers.

Values:

enumerator kStatusGroup_Generic

Group number for generic status codes.

enumerator kStatusGroup_FLASH

Group number for FLASH status codes.

enumerator kStatusGroup_LPSPI

Group number for LPSPI status codes.

enumerator kStatusGroup_FLEXIO_SPI
Group number for FLEXIO SPI status codes.

enumerator kStatusGroup_DSPI
Group number for DSPI status codes.

enumerator kStatusGroup_FLEXIO_UART
Group number for FLEXIO UART status codes.

enumerator kStatusGroup_FLEXIO_I2C
Group number for FLEXIO I2C status codes.

enumerator kStatusGroup_LPI2C
Group number for LPI2C status codes.

enumerator kStatusGroup_UART
Group number for UART status codes.

enumerator kStatusGroup_I2C
Group number for UART status codes.

enumerator kStatusGroup_LPSCI
Group number for LPSCI status codes.

enumerator kStatusGroup_LPUART
Group number for LPUART status codes.

enumerator kStatusGroup_SPI
Group number for SPI status code.

enumerator kStatusGroup_XRDC
Group number for XRDC status code.

enumerator kStatusGroup_SEMA42
Group number for SEMA42 status code.

enumerator kStatusGroup_SDHC
Group number for SDHC status code

enumerator kStatusGroup_SDMMC
Group number for SDMMC status code

enumerator kStatusGroup_SAI
Group number for SAI status code

enumerator kStatusGroup_MCG
Group number for MCG status codes.

enumerator kStatusGroup_SCG
Group number for SCG status codes.

enumerator kStatusGroup_SDSPI
Group number for SDSPI status codes.

enumerator kStatusGroup_FLEXIO_I2S
Group number for FLEXIO I2S status codes

enumerator kStatusGroup_FLEXIO_MCULCD
Group number for FLEXIO LCD status codes

enumerator kStatusGroup_FLASHIAP
Group number for FLASHIAP status codes

enumerator kStatusGroup_FLEXCOMM_I2C
Group number for FLEXCOMM I2C status codes

enumerator kStatusGroup_I2S
Group number for I2S status codes

enumerator kStatusGroup_IUART
Group number for IUART status codes

enumerator kStatusGroup_CSI
Group number for CSI status codes

enumerator kStatusGroup_MIPI_DSI
Group number for MIPI DSI status codes

enumerator kStatusGroup_SDRAMC
Group number for SDRAMC status codes.

enumerator kStatusGroup_POWER
Group number for POWER status codes.

enumerator kStatusGroup_ENET
Group number for ENET status codes.

enumerator kStatusGroup_PHY
Group number for PHY status codes.

enumerator kStatusGroup_TRGMUX
Group number for TRGMUX status codes.

enumerator kStatusGroup_SMARTCARD
Group number for SMARTCARD status codes.

enumerator kStatusGroup_LMEM
Group number for LMEM status codes.

enumerator kStatusGroup_QSPI
Group number for QSPI status codes.

enumerator kStatusGroup_DMA
Group number for DMA status codes.

enumerator kStatusGroup_EDMA
Group number for EDMA status codes.

enumerator kStatusGroup_DMAMGR
Group number for DMAMGR status codes.

enumerator kStatusGroup_FLEXCAN
Group number for FlexCAN status codes.

enumerator kStatusGroup_LTC
Group number for LTC status codes.

enumerator kStatusGroup_FLEXIO_CAMERA
Group number for FLEXIO CAMERA status codes.

enumerator kStatusGroup_LPC_SPI
Group number for LPC_SPI status codes.

enumerator kStatusGroup_LPC_USART
Group number for LPC_USART status codes.

enumerator kStatusGroup_DMIC
Group number for DMIC status codes.

enumerator kStatusGroup_SDIF
Group number for SDIF status codes.

enumerator kStatusGroup_SPIFI
Group number for SPIFI status codes.

enumerator kStatusGroup_OTP
Group number for OTP status codes.

enumerator kStatusGroup_MCAN
Group number for MCAN status codes.

enumerator kStatusGroup_CAAM
Group number for CAAM status codes.

enumerator kStatusGroup_ECSPI
Group number for ECSPI status codes.

enumerator kStatusGroup_USDHC
Group number for USDHC status codes.

enumerator kStatusGroup_LPC_I2C
Group number for LPC_I2C status codes.

enumerator kStatusGroup_DCP
Group number for DCP status codes.

enumerator kStatusGroup_MSCAN
Group number for MSCAN status codes.

enumerator kStatusGroup_ESAI
Group number for ESAI status codes.

enumerator kStatusGroup_FLEXSPI
Group number for FLEXSPI status codes.

enumerator kStatusGroup_MMDC
Group number for MMDC status codes.

enumerator kStatusGroup_PDM
Group number for MIC status codes.

enumerator kStatusGroup_SDMA
Group number for SDMA status codes.

enumerator kStatusGroup_ICS
Group number for ICS status codes.

enumerator kStatusGroup_SPDIF
Group number for SPDIF status codes.

enumerator kStatusGroup_LPC_MINISPI
Group number for LPC_MINISPI status codes.

enumerator kStatusGroup_HASHCRYPT
Group number for Hashcrypt status codes

enumerator kStatusGroup_LPC_SPI_SSP
Group number for LPC_SPI_SSP status codes.

enumerator kStatusGroup_I3C
Group number for I3C status codes

enumerator kStatusGroup_LPC_I2C_1
Group number for LPC_I2C_1 status codes.

enumerator kStatusGroup_NOTIFIER
Group number for NOTIFIER status codes.

enumerator kStatusGroup_DebugConsole
Group number for debug console status codes.

enumerator kStatusGroup_SEMC
Group number for SEMC status codes.

enumerator kStatusGroup_ApplicationRangeStart
Starting number for application groups.

enumerator kStatusGroup_IAP
Group number for IAP status codes

enumerator kStatusGroup_SFA
Group number for SFA status codes

enumerator kStatusGroup_SPC
Group number for SPC status codes.

enumerator kStatusGroup_PUF
Group number for PUF status codes.

enumerator kStatusGroup_TOUCH_PANEL
Group number for touch panel status codes

enumerator kStatusGroup_VBAT
Group number for VBAT status codes

enumerator kStatusGroup_XSPI
Group number for XSPI status codes

enumerator kStatusGroup_PNGDEC
Group number for PNGDEC status codes

enumerator kStatusGroup_JPEGDEC
Group number for JPEGDEC status codes

enumerator kStatusGroup_AUDMIX
Group number for AUDMIX status codes

enumerator kStatusGroup_HAL_GPIO
Group number for HAL GPIO status codes.

enumerator kStatusGroup_HAL_UART
Group number for HAL UART status codes.

enumerator kStatusGroup_HAL_TIMER
Group number for HAL TIMER status codes.

enumerator kStatusGroup_HAL_SPI
Group number for HAL SPI status codes.

enumerator kStatusGroup_HAL_I2C
Group number for HAL I2C status codes.

enumerator kStatusGroup_HAL_FLASH
Group number for HAL FLASH status codes.

enumerator kStatusGroup_HAL_PWM
Group number for HAL PWM status codes.

enumerator kStatusGroup_HAL_RNG
Group number for HAL RNG status codes.

enumerator kStatusGroup_HAL_I2S
Group number for HAL I2S status codes.

enumerator kStatusGroup_HAL_ADC_SENSOR
Group number for HAL ADC SENSOR status codes.

enumerator kStatusGroup_TIMERMANAGER
Group number for TiMER MANAGER status codes.

enumerator kStatusGroup_SERIALMANAGER
Group number for SERIAL MANAGER status codes.

enumerator kStatusGroup_LED
Group number for LED status codes.

enumerator kStatusGroup_BUTTON
Group number for BUTTON status codes.

enumerator kStatusGroup_EXTERN_EEPROM
Group number for EXTERN EEPROM status codes.

enumerator kStatusGroup_SHELL
Group number for SHELL status codes.

enumerator kStatusGroup_MEM_MANAGER
Group number for MEM MANAGER status codes.

enumerator kStatusGroup_LIST
Group number for List status codes.

enumerator kStatusGroup_OSA
Group number for OSA status codes.

enumerator kStatusGroup_COMMON_TASK
Group number for Common task status codes.

enumerator kStatusGroup_MSG
Group number for messaging status codes.

enumerator kStatusGroup_SDK_OCOTP
Group number for OCOTP status codes.

enumerator kStatusGroup_SDK_FLEXSPINOR
Group number for FLEXSPINOR status codes.

enumerator kStatusGroup_CODEC
Group number for codec status codes.

enumerator kStatusGroup_ASRC
Group number for codec status ASRC.

enumerator kStatusGroup_OTFAD
Group number for codec status codes.

enumerator kStatusGroup_SDIOSLV
Group number for SDIOSLV status codes.

enumerator kStatusGroup_MECC
Group number for MECC status codes.

enumerator kStatusGroup_ENET_QOS
Group number for ENET_QOS status codes.

enumerator kStatusGroup_LOG
Group number for LOG status codes.

enumerator kStatusGroup_I3CBUS
Group number for I3CBUS status codes.

enumerator kStatusGroup_QSCI
Group number for QSCI status codes.

enumerator kStatusGroup_ELEMU
Group number for ELEMU status codes.

enumerator kStatusGroup_QUEUEDSPI
Group number for QSPI status codes.

enumerator kStatusGroup_POWER_MANAGER
Group number for POWER_MANAGER status codes.

enumerator kStatusGroup_IPED
Group number for IPED status codes.

enumerator kStatusGroup_ELS_PKC
Group number for ELS PKC status codes.

enumerator kStatusGroup_CSS_PKC
Group number for CSS PKC status codes.

enumerator kStatusGroup_HOSTIF
Group number for HOSTIF status codes.

enumerator kStatusGroup_CLIF
Group number for CLIF status codes.

enumerator kStatusGroup_BMA
Group number for BMA status codes.

enumerator kStatusGroup_NETC
Group number for NETC status codes.

enumerator kStatusGroup_ELE
Group number for ELE status codes.

enumerator kStatusGroup_GLIKEY
Group number for GLIKEY status codes.

enumerator kStatusGroup_AON_POWER
Group number for AON_POWER status codes.

enumerator kStatusGroup_AON_COMMON
Group number for AON_COMMON status codes.

enumerator kStatusGroup_ENDAT3
Group number for ENDAT3 status codes.

enumerator kStatusGroup_HIPERFACE
Group number for HIPERFACE status codes.

enumerator kStatusGroup_NPX
Group number for NPX status codes.

enumerator kStatusGroup_ELA_CSEC
Group number for ELA_CSEC status codes.

enumerator kStatusGroup_FLEXIO_T_FORMAT
Group number for T-format status codes.

enumerator kStatusGroup_FLEXIO_A_FORMAT
Group number for A-format status codes.

enumerator kStatusGroup_LPC_QSPI
Group number for LPC QSPI status codes.

enumerator kStatusGroup_EVENT_CTRL
Group number for Event controller status codes.

Generic status return codes.

Values:

enumerator kStatus_Success
Generic status for Success.

enumerator kStatus_Fail
Generic status for Fail.

enumerator kStatus_ReadOnly
Generic status for read only failure.

enumerator kStatus_OutOfRange
Generic status for out of range access.

enumerator kStatus_InvalidArgument
Generic status for invalid argument check.

enumerator kStatus_Timeout
Generic status for timeout.

enumerator kStatus_NoTransferInProgress
Generic status for no transfer in progress.

enumerator kStatus_Busy
Generic status for module is busy.

enumerator kStatus_NoData
Generic status for no data is found for the operation.

typedef int32_t status_t
Type used for all status and error return values.

void *SDK_Malloc(size_t size, size_t alignbytes)

Allocate memory with given alignment and aligned size.

This is provided to support the dynamically allocated memory used in cache-able region.

Parameters

- size – The length required to malloc.
- alignbytes – The alignment size.

Return values

The – allocated memory.

void SDK_Free(void *ptr)

Free memory.

Parameters

- ptr – The memory to be release.

void SDK_DelayAtLeastUs(uint32_t delayTime_us, uint32_t coreClock_Hz)

Delay at least for some time. Please note that, this API uses while loop for delay, different run-time environments make the time not precise, if precise delay count was needed, please implement a new delay function with hardware timer.

Parameters

- delayTime_us – Delay time in unit of microsecond.
- coreClock_Hz – Core clock frequency with Hz.

static inline *status_t* EnableIRQ(IRQn_Type interrupt)

Enable specific interrupt.

Enable LEVEL1 interrupt. For some devices, there might be multiple interrupt levels. For example, there are NVIC and intmux. Here the interrupts connected to NVIC are the LEVEL1 interrupts, because they are routed to the core directly. The interrupts connected to intmux are the LEVEL2 interrupts, they are routed to NVIC first then routed to core.

This function only enables the LEVEL1 interrupts. The number of LEVEL1 interrupts is indicated by the feature macro FSL_FEATURE_NUMBER_OF_LEVEL1_INT_VECTORS.

Parameters

- interrupt – The IRQ number.

Return values

- kStatus_Success – Interrupt enabled successfully
- kStatus_Fail – Failed to enable the interrupt

static inline *status_t* DisableIRQ(IRQn_Type interrupt)

Disable specific interrupt.

Disable LEVEL1 interrupt. For some devices, there might be multiple interrupt levels. For example, there are NVIC and intmux. Here the interrupts connected to NVIC are the LEVEL1 interrupts, because they are routed to the core directly. The interrupts connected to intmux are the LEVEL2 interrupts, they are routed to NVIC first then routed to core.

This function only disables the LEVEL1 interrupts. The number of LEVEL1 interrupts is indicated by the feature macro FSL_FEATURE_NUMBER_OF_LEVEL1_INT_VECTORS.

Parameters

- interrupt – The IRQ number.

Return values

- kStatus_Success – Interrupt disabled successfully
- kStatus_Fail – Failed to disable the interrupt

static inline *status_t* EnableIRQWithPriority(IRQn_Type interrupt, uint8_t priNum)

Enable the IRQ, and also set the interrupt priority.

Only handle LEVEL1 interrupt. For some devices, there might be multiple interrupt levels. For example, there are NVIC and intmux. Here the interrupts connected to NVIC are the LEVEL1 interrupts, because they are routed to the core directly. The interrupts connected to intmux are the LEVEL2 interrupts, they are routed to NVIC first then routed to core.

This function only handles the LEVEL1 interrupts. The number of LEVEL1 interrupts is indicated by the feature macro FSL_FEATURE_NUMBER_OF_LEVEL1_INT_VECTORS.

Parameters

- interrupt – The IRQ to Enable.
- priNum – Priority number set to interrupt controller register.

Return values

- kStatus_Success – Interrupt priority set successfully
- kStatus_Fail – Failed to set the interrupt priority.

static inline *status_t* IRQ_SetPriority(IRQn_Type interrupt, uint8_t priNum)

Set the IRQ priority.

Only handle LEVEL1 interrupt. For some devices, there might be multiple interrupt levels. For example, there are NVIC and intmux. Here the interrupts connected to NVIC are the LEVEL1 interrupts, because they are routed to the core directly. The interrupts connected to intmux are the LEVEL2 interrupts, they are routed to NVIC first then routed to core.

This function only handles the LEVEL1 interrupts. The number of LEVEL1 interrupts is indicated by the feature macro FSL_FEATURE_NUMBER_OF_LEVEL1_INT_VECTORS.

Parameters

- interrupt – The IRQ to set.
- priNum – Priority number set to interrupt controller register.

Return values

- kStatus_Success – Interrupt priority set successfully
- kStatus_Fail – Failed to set the interrupt priority.

static inline *status_t* IRQ_ClearPendingIRQ(IRQn_Type interrupt)

Clear the pending IRQ flag.

Only handle LEVEL1 interrupt. For some devices, there might be multiple interrupt levels. For example, there are NVIC and intmux. Here the interrupts connected to NVIC are the LEVEL1 interrupts, because they are routed to the core directly. The interrupts connected to intmux are the LEVEL2 interrupts, they are routed to NVIC first then routed to core.

This function only handles the LEVEL1 interrupts. The number of LEVEL1 interrupts is indicated by the feature macro FSL_FEATURE_NUMBER_OF_LEVEL1_INT_VECTORS.

Parameters

- interrupt – The flag which IRQ to clear.

Return values

- kStatus_Success – Interrupt priority set successfully
- kStatus_Fail – Failed to set the interrupt priority.

static inline uint32_t DisableGlobalIRQ(void)

Disable the global IRQ.

Disable the global interrupt and return the current primask register. User is required to provided the primask register for the *EnableGlobalIRQ()*.

Returns

Current primask value.

static inline void EnableGlobalIRQ(uint32_t primask)

Enable the global IRQ.

Set the primask register with the provided primask value but not just enable the primask. The idea is for the convenience of integration of RTOS. some RTOS get its own management mechanism of primask. User is required to use the *EnableGlobalIRQ()* and *DisableGlobalIRQ()* in pair.

Parameters

- primask – value of primask register to be restored. The primask value is supposed to be provided by the *DisableGlobalIRQ()*.

static inline bool __SDK_AtomicLocalCompareAndSet(uint32_t *addr, uint32_t expected, uint32_t newValue)

static inline uint32_t __SDK_AtomicTestAndSet(uint32_t *addr, uint32_t newValue)

FSL_DRIVER_TRANSFER_DOUBLE_WEAK_IRQ

Macro to use the default weak IRQ handler in drivers.

MAKE_STATUS(group, code)

Construct a status code value from a group and code number.

MAKE_VERSION(major, minor, bugfix)

Construct the version number for drivers.

The driver version is a 32-bit number, for both 32-bit platforms(such as Cortex M) and 16-bit platforms(such as DSC).

```
| Unused    || Major Version || Minor Version ||  Bug Fix    |
31       25  24          17  16          9  8           0
```

ARRAY_SIZE(x)

Computes the number of elements in an array.

SUPPRESS_FALL_THROUGH_WARNING()

For switch case code block, if case section ends without “break;” statement, there wil be fallthrough warning with compiler flag -Wextra or -Wimplicit-fallthrough=n when using armgcc. To suppress this warning, “SUPPRESS_FALL_THROUGH_WARNING();” need to be added at the end of each case section which misses “break;”statement.

MSDK_REG_SECURE_ADDR(x)

Convert the register address to the one used in secure mode.

MSDK_REG_NONSECURE_ADDR(x)

Convert the register address to the one used in non-secure mode.

MSDK_HAS_DWT_CYCCNT

The chip supports DWT CYCCNT or not.

MSDK_INVALID_IRQ_HANDLER

Invalid IRQ handler address.

2.46 LPADC: 12-bit SAR Analog-to-Digital Converter Driver

enum _lpadc_status_flags

Define hardware flags of the module.

Values:

enumerator kLPADC_ResultFIFO0OverflowFlag

Indicates that more data has been written to the Result FIFO 0 than it can hold.

enumerator kLPADC_ResultFIFO0ReadyFlag

Indicates when the number of valid datawords in the result FIFO 0 is greater than the setting watermark level.

enumerator kLPADC_TriggerExceptionFlag

Indicates that a trigger exception event has occurred.

enumerator kLPADC_TriggerCompletionFlag

Indicates that a trigger completion event has occurred.

enumerator kLPADC_CalibrationReadyFlag

Indicates that the calibration process is done.

enumerator kLPADC_ActiveFlag

Indicates that the ADC is in active state.

enumerator kLPADC_ResultFIFOOverflowFlag

To compilitable with old version, do not recommend using this, please use *kLPADC_ResultFIFO0OverflowFlag* as instead.

enumerator kLPADC_ResultFIFOReadyFlag

To compilitable with old version, do not recommend using this, please use *kLPADC_ResultFIFO0ReadyFlag* as instead.

enum _lpadc_interrupt_enable

Define interrupt switchers of the module.

Note: LPADC of different chips supports different number of trigger sources, please check the Reference Manual for details.

Values:

enumerator kLPADC_ResultFIFO0OverflowInterruptEnable

Configures ADC to generate overflow interrupt requests when FOF0 flag is asserted.

enumerator kLPADC_FIFO0WatermarkInterruptEnable

Configures ADC to generate watermark interrupt requests when RDY0 flag is asserted.

enumerator kLPADC_ResultFIFOOverflowInterruptEnable

To compilitable with old version, do not recommend using this, please use *kLPADC_ResultFIFO0OverflowInterruptEnable* as instead.

enumerator kLPADC_FIFOWatermarkInterruptEnable

To compilitable with old version, do not recommend using this, please use *kLPADC_FIFO0WatermarkInterruptEnable* as instead.

enumerator kLPADC_TriggerExceptionInterruptEnable

Configures ADC to generate trigger exception interrupt.

enumerator kLPADC_Trigger0CompletionInterruptEnable

Configures ADC to generate interrupt when trigger 0 completion.

enumerator kLPADC_Trigger1CompletionInterruptEnable

Configures ADC to generate interrupt when trigger 1 completion.

enum _lpadc_trigger_status_flags

The enumerator of lpadc trigger status flags, including interrupted flags and completed flags.

Note: LPADC of different chips supports different number of trigger sources, please check the Reference Manual for details.

Values:

enumerator kLPADC_Trigger0InterruptedFlag

Trigger 0 is interrupted by a high priority exception.

enumerator kLPADC_Trigger1InterruptedFlag

Trigger 1 is interrupted by a high priority exception.

enumerator kLPADC_Trigger0CompletedFlag

Trigger 0 is completed and trigger 0 has enabled completion interrupts.

enumerator kLPADC_Trigger1CompletedFlag

Trigger 1 is completed and trigger 1 has enabled completion interrupts.

enum _lpadc_sample_scale_mode

Define enumeration of sample scale mode.

The sample scale mode is used to reduce the selected ADC analog channel input voltage level by a factor. The maximum possible voltage on the ADC channel input should be considered when selecting a scale mode to ensure that the reducing factor always results voltage level at or below the VREFH reference. This reducing capability allows conversion of analog inputs higher than VREFH. A-side and B-side channel inputs are both scaled using the scale mode.

Values:

enumerator kLPADC_SamplePartScale

Use divided input voltage signal. (For scale select,please refer to the reference manual).

enumerator kLPADC_SampleFullScale

Full scale (Factor of 1).

enum _lpadc_sample_channel_mode

Define enumeration of channel sample mode.

The channel sample mode configures the channel with single-end/differential/dual-single-end, side A/B.

Values:

enumerator kLPADC_SampleChannelSingleEndSideA

Single-end mode, only A-side channel is converted.

enumerator kLPADC_SampleChannelSingleEndSideB

Single-end mode, only B-side channel is converted.

enumerator kLPADC_SampleChannelDiffBothSideAB

Differential mode, the ADC result is (CHnA-CHnB).

enumerator kLPADC_SampleChannelDiffBothSideBA

Differential mode, the ADC result is (CHnB-CHnA).

enumerator kLPADC_SampleChannelDiffBothSide

Differential mode, the ADC result is (CHnA-CHnB).

enumerator kLPADC_SampleChannelDualSingleEndBothSide

Dual-Single-Ended Mode. Both A side and B side channels are converted independently.

enum _lpadc_hardware_average_mode

Define enumeration of hardware average selection.

It Selects how many ADC conversions are averaged to create the ADC result. An internal storage buffer is used to capture temporary results while the averaging iterations are executed.

Note: Some enumerator values are not available on some devices, mainly depends on the size of AVGS field in CMDH register.

Values:

enumerator kLPADC_HardwareAverageCount1

Single conversion.

enumerator kLPADC_HardwareAverageCount2

2 conversions averaged.

enumerator kLPADC_HardwareAverageCount4

4 conversions averaged.

enumerator kLPADC_HardwareAverageCount8

8 conversions averaged.

enumerator kLPADC_HardwareAverageCount16
16 conversions averaged.

enumerator kLPADC_HardwareAverageCount32
32 conversions averaged.

enumerator kLPADC_HardwareAverageCount64
64 conversions averaged.

enumerator kLPADC_HardwareAverageCount128
128 conversions averaged.

enum _lpadc_sample_time_mode
Define enumeration of sample time selection.

The shortest sample time maximizes conversion speed for lower impedance inputs. Extending sample time allows higher impedance inputs to be accurately sampled. Longer sample times can also be used to lower overall power consumption when command looping and sequencing is configured and high conversion rates are not required.

Values:

enumerator kLPADC_SampleTimeADCK3
3 ADCK cycles total sample time.

enumerator kLPADC_SampleTimeADCK5
5 ADCK cycles total sample time.

enumerator kLPADC_SampleTimeADCK7
7 ADCK cycles total sample time.

enumerator kLPADC_SampleTimeADCK11
11 ADCK cycles total sample time.

enumerator kLPADC_SampleTimeADCK19
19 ADCK cycles total sample time.

enumerator kLPADC_SampleTimeADCK35
35 ADCK cycles total sample time.

enumerator kLPADC_SampleTimeADCK67
69 ADCK cycles total sample time.

enumerator kLPADC_SampleTimeADCK131
131 ADCK cycles total sample time.

enum _lpadc_hardware_compare_mode
Define enumeration of hardware compare mode.

After an ADC channel input is sampled and converted and any averaging iterations are performed, this mode setting guides operation of the automatic compare function to optionally

only store when the compare operation is true. When compare is enabled, the conversion result is compared to the compare values.

Values:

enumerator kLPADC_HardwareCompareDisabled

Compare disabled.

enumerator kLPADC_HardwareCompareStoreOnTrue

Compare enabled. Store on true.

enumerator kLPADC_HardwareCompareRepeatUntilTrue

Compare enabled. Repeat channel acquisition until true.

enum _lpadc_conversion_resolution_mode

Define enumeration of conversion resolution mode.

Configure the resolution bit in specific conversion type. For detailed resolution accuracy, see to *lpadc_sample_channel_mode_t*

Values:

enumerator kLPADC_ConversionResolutionStandard

Standard resolution. Single-ended 12-bit conversion, Differential 13-bit conversion with 2's complement output.

enumerator kLPADC_ConversionResolutionHigh

High resolution. Single-ended 16-bit conversion; Differential 16-bit conversion with 2's complement output.

enum _lpadc_conversion_average_mode

Define enumeration of conversion averages mode.

Configure the converion average number for auto-calibration.

Note: Some enumerator values are not available on some devices, mainly depends on the size of CAL_AVGS field in CTRL register.

Values:

enumerator kLPADC_ConversionAverage1

Single conversion.

enumerator kLPADC_ConversionAverage2

2 conversions averaged.

enumerator kLPADC_ConversionAverage4

4 conversions averaged.

enumerator kLPADC_ConversionAverage8

8 conversions averaged.

enumerator kLPADC_ConversionAverage16
16 conversions averaged.

enumerator kLPADC_ConversionAverage32
32 conversions averaged.

enumerator kLPADC_ConversionAverage64
64 conversions averaged.

enumerator kLPADC_ConversionAverage128
128 conversions averaged.

enumerator kLPADC_ConversionAverageMax

enum _lpadc_reference_voltage_mode
Define enumeration of reference voltage source.

For detail information, need to check the SoC's specification.

Values:

enumerator kLPADC_ReferenceVoltageAlt1
Option 1 setting.

enumerator kLPADC_ReferenceVoltageAlt2
Option 2 setting.

enumerator kLPADC_ReferenceVoltageAlt3
Option 3 setting.

enum _lpadc_power_level_mode
Define enumeration of power configuration.

Configures the ADC for power and performance. In the highest power setting the highest conversion rates will be possible. Refer to the device data sheet for power and performance capabilities for each setting.

Values:

enumerator kLPADC_PowerLevelAlt1
Lowest power setting.

enumerator kLPADC_PowerLevelAlt2
Next lowest power setting.

enumerator kLPADC_PowerLevelAlt3
...

enumerator kLPADC_PowerLevelAlt4
Highest power setting.

enum _lpadc_offset_calibration_mode

Define enumeration of offset calibration mode.

Values:

enumerator kLPADC_OffsetCalibration12bitMode

12 bit offset calibration mode.

enumerator kLPADC_OffsetCalibration16bitMode

16 bit offset calibration mode.

enum _lpadc_trigger_priority_policy

Define enumeration of trigger priority policy.

This selection controls how higher priority triggers are handled.

Note: kLPADC_TriggerPriorityPreemptSubsequently is not available on some devices, mainly depends on the size of TPRICTRL field in CFG register.

Values:

enumerator kLPADC_ConvPreemptImmediatelyNotAutoResumed

If a higher priority trigger is detected during command processing, the current conversion is aborted and the new command specified by the trigger is started, when higher priority conversion finishes, the preempted conversion is not automatically resumed or restarted.

enumerator kLPADC_ConvPreemptSoftlyNotAutoResumed

If a higher priority trigger is received during command processing, the current conversion is completed (including averaging iterations and compare function if enabled) and stored to the result FIFO before the higher priority trigger/command is initiated, when higher priority conversion finishes, the preempted conversion is not resumed or restarted.

enumerator kLPADC_ConvPreemptImmediatelyAutoRestarted

If a higher priority trigger is detected during command processing, the current conversion is aborted and the new command specified by the trigger is started, when higher priority conversion finishes, the preempted conversion will automatically be restarted.

enumerator kLPADC_ConvPreemptSoftlyAutoRestarted

If a higher priority trigger is received during command processing, the current conversion is completed (including averaging iterations and compare function if enabled) and stored to the result FIFO before the higher priority trigger/command is initiated, when higher priority conversion finishes, the preempted conversion will automatically be restarted.

enumerator kLPADC_ConvPreemptImmediatelyAutoResumed

If a higher priority trigger is detected during command processing, the current conversion is aborted and the new command specified by the trigger is started, when higher priority conversion finishes, the preempted conversion will automatically be resumed.

enumerator kLPADC_ConvPreemptSoftlyAutoResumed

If a higher priority trigger is received during command processing, the current conversion is completed (including averaging iterations and compare function if enabled) and stored to the result FIFO before the higher priority trigger/command is initiated, when higher priority conversion finishes, the preempted conversion will be automatically be resumed.

enumerator kLPADC_TriggerPriorityPreemptImmediately

Legacy support is not recommended as it only ensures compatibility with older versions.

enumerator kLPADC_TriggerPriorityPreemptSoftly

Legacy support is not recommended as it only ensures compatibility with older versions.

enumerator kLPADC_TriggerPriorityExceptionDisabled

High priority trigger exception disabled.

enum _lpadc_tune_value

Define enumeration of tune value.

Values:

enumerator kLPADC_TuneValue0

Tune value 0.

enumerator kLPADC_TuneValue1

Tune value 1.

enumerator kLPADC_TuneValue2

Tune value 2.

enumerator kLPADC_TuneValue3

Tune value 3.

typedef enum *_lpadc_sample_scale_mode* lpadc_sample_scale_mode_t

Define enumeration of sample scale mode.

The sample scale mode is used to reduce the selected ADC analog channel input voltage level by a factor. The maximum possible voltage on the ADC channel input should be considered when selecting a scale mode to ensure that the reducing factor always results voltage level at or below the VREFH reference. This reducing capability allows conversion of analog inputs higher than VREFH. A-side and B-side channel inputs are both scaled using the scale mode.

typedef enum *_lpadc_sample_channel_mode* lpadc_sample_channel_mode_t

Define enumeration of channel sample mode.

The channel sample mode configures the channel with single-end/differential/dual-single-end, side A/B.

typedef enum *_lpadc_hardware_average_mode* lpadc_hardware_average_mode_t

Define enumeration of hardware average selection.

It Selects how many ADC conversions are averaged to create the ADC result. An internal storage buffer is used to capture temporary results while the averaging iterations are executed.

Note: Some enumerator values are not available on some devices, mainly depends on the size of AVGS field in CMDH register.

---

typedef enum *_lpadc_sample_time_mode* lpadc_sample_time_mode_t

Define enumeration of sample time selection.

The shortest sample time maximizes conversion speed for lower impedance inputs. Extending sample time allows higher impedance inputs to be accurately sampled. Longer sample times can also be used to lower overall power consumption when command looping and sequencing is configured and high conversion rates are not required.

typedef enum *_lpadc_hardware_compare_mode* lpadc_hardware_compare_mode_t

Define enumeration of hardware compare mode.

After an ADC channel input is sampled and converted and any averaging iterations are performed, this mode setting guides operation of the automatic compare function to optionally only store when the compare operation is true. When compare is enabled, the conversion result is compared to the compare values.

typedef enum *_lpadc_conversion_resolution_mode* lpadc_conversion_resolution_mode_t

Define enumeration of conversion resolution mode.

Configure the resolution bit in specific conversion type. For detailed resolution accuracy, see to *lpadc_sample_channel_mode_t*

typedef enum *_lpadc_conversion_average_mode* lpadc_conversion_average_mode_t

Define enumeration of conversion averages mode.

Configure the converion average number for auto-calibration.

Note: Some enumerator values are not available on some devices, mainly depends on the size of CAL_AVGS field in CTRL register.

---

typedef enum *_lpadc_reference_voltage_mode* lpadc_reference_voltage_source_t

Define enumeration of reference voltage source.

For detail information, need to check the SoC's specification.

typedef enum *_lpadc_power_level_mode* lpadc_power_level_mode_t

Define enumeration of power configuration.

Configures the ADC for power and performance. In the highest power setting the highest conversion rates will be possible. Refer to the device data sheet for power and performance capabilities for each setting.

typedef enum *_lpadc_offset_calibration_mode* lpadc_offset_calibration_mode_t

Define enumeration of offset calibration mode.

typedef enum *_lpadc_trigger_priority_policy* lpadc_trigger_priority_policy_t

Define enumeration of trigger priority policy.

This selection controls how higher priority triggers are handled.

Note: **kLPADC_TriggerPriorityPreemptSubsequently** is not available on some devices, mainly depends on the size of TPRICTRL field in CFG register.

---

typedef enum *_lpadc_tune_value* lpadc_tune_value_t

Define enumeration of tune value.

typedef struct *_lpadc_calibration_value* lpadc_calibration_value_t

A structure of calibration value.

LPADC_CONVERSION_COMPLETE_TIMEOUT

Max loops to wait for LPADC conversion complete.

When doing calibration, driver will wait for the completion of conversion. This parameter defines how many loops to check completion before return timeout. If defined as 0, driver will wait forever until completion.

LPADC_CALIBRATION_READY_TIMEOUT

Max loops to wait for LPADC calibration ready.

Before doing calibration, driver will wait for the calibration ready. This parameter defines how many loops to check the calibration ready. If defined as 0, driver will wait forever until ready.

LPADC_GAIN_CAL_READY_TIMEOUT

Max loops to wait for LPADC gain calibration GAIN_CAL ready.

Before doing calibration, driver will wait for the gain calibration GAIN_CAL ready. This parameter defines how many loops to check the gain calibration GAIN_CAL ready. If defined as 0, driver will wait forever until ready.

LPADC_USE_FIXED_POINT_GAIN_CALCULATION

Use fixed point arithmetic for the auto-calibration gain calculation.

When set to 1, *LPADC_FinishAutoCalibration()* calculates the gain conversion result with integer-only arithmetic instead of the float/double software library, which saves several kB of flash on code size sensitive devices. The fixed point result keeps the gain fraction in Q17.14, so the two least significant bits of the gain conversion result are always zero.

ADC_OFSTRIM_OFSTRIM_MAX

ADC_OFSTRIM_OFSTRIM_SIGN

LPADC_GET_ACTIVE_COMMAND_STATUS(statusVal)

Define the MACRO function to get command status from status value.

The statusVal is the return value from *LPADC_GetStatusFlags()*.

LPADC_GET_ACTIVE_TRIGGER_STATUE(statusVal)

Define the MACRO function to get trigger status from status value.

The statusVal is the return value from *LPADC_GetStatusFlags()*.

void LPADC_Init(ADC_Type *base, const *lpadc_config_t* *config)

Initializes the LPADC module.

Parameters

- base – LPADC peripheral base address.
- config – Pointer to configuration structure. See "lpadc_config_t".

void LPADC_GetDefaultConfig(*lpadc_config_t* *config)

Gets an available pre-defined settings for initial configuration.

This function initializes the converter configuration structure with an available settings. The default values are:

```
config->enableInDozeMode        = true;
config->enableAnalogPreliminary = false;
config->powerUpDelay            = 0x80;
config->referenceVoltageSource  = kLPADC_ReferenceVoltageAlt1;
config->powerLevelMode          = kLPADC_PowerLevelAlt1;
config->triggerPriorityPolicy   = kLPADC_TriggerPriorityPreemptImmediately;
config->enableConvPause         = false;
config->convPauseDelay          = 0U;
config->FIFOWatermark           = 0U;
```

Parameters

- config – Pointer to configuration structure.

void LPADC_Deinit(ADC_Type *base)

De-initializes the LPADC module.

Parameters

- base – LPADC peripheral base address.

static inline void LPADC_Enable(ADC_Type *base, bool enable)

Switch on/off the LPADC module.

Parameters

- base – LPADC peripheral base address.
- enable – switcher to the module.

static inline void LPADC_DoResetFIFO(ADC_Type *base)

Do reset the conversion FIFO.

Parameters

- base – LPADC peripheral base address.

static inline void LPADC_DoResetConfig(ADC_Type *base)

Do reset the module's configuration.

Reset all ADC internal logic and registers, except the Control Register (ADCx_CTRL).

Parameters

- base – LPADC peripheral base address.

static inline uint32_t LPADC_GetStatusFlags(ADC_Type *base)

Get status flags.

Parameters

- base – LPADC peripheral base address.

Returns
status flags' mask. See to *_lpadc_status_flags*.

static inline void LPADC_ClearStatusFlags(ADC_Type *base, uint32_t mask)

Clear status flags.

Only the flags can be cleared by writing ADCx_STATUS register would be cleared by this API.

Parameters

- base – LPADC peripheral base address.
- mask – Mask value for flags to be cleared. See to *_lpadc_status_flags*.

static inline uint32_t LPADC_GetTriggerStatusFlags(ADC_Type *base)

Get trigger status flags to indicate which trigger sequences have been completed or interrupted by a high priority trigger exception.

Note: On some devices, the trigger completion status may be asserted before the final command in a chained trigger sequence starts to execute. When using chained commands, do not rely on trigger completion status alone to guarantee that all conversion results are already available in the FIFO. Use FIFO ready indication together with result tags, or stall the last command with WAIT_TRIG when that sequencing model is acceptable for the application.

Parameters

- base – LPADC peripheral base address.

Returns
The OR'ed value of *_lpadc_trigger_status_flags*.

static inline void LPADC_ClearTriggerStatusFlags(ADC_Type *base, uint32_t mask)

Clear trigger status flags.

Parameters

- base – LPADC peripheral base address.
- mask – The mask of trigger status flags to be cleared, should be the OR'ed value of *_lpadc_trigger_status_flags*.

static inline void LPADC_EnableInterrupts(ADC_Type *base, uint32_t mask)

Enable interrupts.

Note: When enabling trigger completion interrupts (kLPADC_TriggerXCompletionInterruptEnable) on some devices, the interrupt may occur before the final command in a chained trigger sequence starts to execute. For multi-command trigger sequences, do not use the trigger completion interrupt alone as the indication that all expected results are already stored in the FIFO.

Parameters

- base – LPADC peripheral base address.
- mask – Mask value for interrupt events. See to *_lpadc_interrupt_enable*.

static inline void LPADC_DisableInterrupts(ADC_Type *base, uint32_t mask)

Disable interrupts.

Parameters

- base – LPADC peripheral base address.
- mask – Mask value for interrupt events. See to *_lpadc_interrupt_enable*.

static inline void LPADC_EnableFIFOWatermarkDMA(ADC_Type *base, bool enable)

Switch on/off the DMA trigger for FIFO watermark event.

Parameters

- base – LPADC peripheral base address.
- enable – Switcher to the event.

static inline uint32_t LPADC_GetConvResultCount(ADC_Type *base)

Get the count of result kept in conversion FIFO.

Parameters

- base – LPADC peripheral base address.

Returns

The count of result kept in conversion FIFO.

bool LPADC_GetConvResult(ADC_Type *base, *lpadc_conv_result_t* *result)

Get the result in conversion FIFO.

Parameters

- base – LPADC peripheral base address.
- result – Pointer to structure variable that keeps the conversion result in conversion FIFO.

Returns

Status whether FIFO entry is valid.

void LPADC_GetConvResultBlocking(ADC_Type *base, *lpadc_conv_result_t* *result)

Get the result in conversion FIFO using blocking method.

Parameters

- base – LPADC peripheral base address.
- result – Pointer to structure variable that keeps the conversion result in conversion FIFO.

void LPADC_SetConvTriggerConfig(ADC_Type *base, uint32_t triggerId, const *lpadc_conv_trigger_config_t* *config)

Configure the conversion trigger source.

Each programmable trigger can launch the conversion command in command buffer.

Parameters

- base – LPADC peripheral base address.
- triggerId – ID for each trigger. Typically, the available value range is from 0.
- config – Pointer to configuration structure. See to *lpadc_conv_trigger_config_t*.

void LPADC_GetDefaultConvTriggerConfig(*lpadc_conv_trigger_config_t* *config)

Gets an available pre-defined settings for trigger's configuration.

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

```
config->targetCommandId       = 0U;
config->delayPower            = 0U;
config->priority              = 0U;
config->channelAFIFOSelect    = 0U;
config->channelBFIFOSelect    = 0U;
config->enableHardwareTrigger = false;
```

Parameters

- config – Pointer to configuration structure.

static inline void LPADC_DoSoftwareTrigger(ADC_Type *base, uint32_t triggerIdMask)

Do software trigger to conversion command.

Parameters

- base – LPADC peripheral base address.
- triggerIdMask – Mask value for software trigger indexes, which count from zero.

static inline void LPADC_EnableHardwareTriggerCommandSelection(ADC_Type *base, uint32_t triggerId, bool enable)

Enable hardware trigger command selection.

This function will use the hardware trigger command from ADC_ETC.The trigger command is then defined by ADC hardware trigger command selection field in ADC_ETC->TRIGx_CHAINy_z_n[CSEL].

Parameters

- base – LPADC peripheral base address.
- triggerId – ID for each trigger. Typically, the available value range is from 0.
- enable – True to enable or flase to disable.

void LPADC_SetConvCommandConfig(ADC_Type *base, uint32_t commandId, const *lpadc_conv_command_config_t* *config)

Configure conversion command.

Note: The number of compare value register on different chips is different, that is mean in some chips, some command buffers do not have the compare functionality.

Parameters

- base – LPADC peripheral base address.
- commandId – ID for command in command buffer. Typically, the available value range is 1 - 15.
- config – Pointer to configuration structure. See to *lpadc_conv_command_config_t*.

void LPADC_GetDefaultConvCommandConfig(*lpadc_conv_command_config_t* *config)

Gets an available pre-defined settings for conversion command's configuration.

This function initializes the conversion command's configuration structure with an available settings. The default values are:

```
config->sampleScaleMode             = kLPADC_SampleFullScale;
config->channelBScaleMode           = kLPADC_SampleFullScale;
config->sampleChannelMode           = kLPADC_SampleChannelSingleEndSideA;
config->channelNumber               = 0U;
config->channelBNumber              = 0U;
config->chainedNextCommandNumber    = 0U;
config->enableAutoChannelIncrement = false;
config->loopCount                   = 0U;
config->hardwareAverageMode         = kLPADC_HardwareAverageCount1;
config->sampleTimeMode              = kLPADC_SampleTimeADCK3;
config->hardwareCompareMode         = kLPADC_HardwareCompareDisabled;
config->hardwareCompareValueHigh    = 0U;
config->hardwareCompareValueLow     = 0U;
config->conversionResolutionMode    = kLPADC_ConversionResolutionStandard;
config->enableWaitTrigger           = false;
config->enableChannelB              = false;
```

Parameters

- config – Pointer to configuration structure.

void LPADC_EnableCalibration(ADC_Type *base, bool enable)

Enable the calibration function.

When CALOFS is set, the ADC is configured to perform a calibration function anytime the ADC executes a conversion. Any channel selected is ignored and the value returned in the RESFIFO is a signed value between -31 and 31. -32 is not a valid and is never a returned value. Software should copy the lower 6- bits of the conversion result stored in the RESFIFO after a completed calibration conversion to the OFSTRIM field. The OFSTRIM field is used in normal operation for offset correction.

Parameters

- base – LPADC peripheral base address.
- enable – switcher to the calibration function.

static inline void LPADC_SetOffsetValue(ADC_Type *base, uint32_t value)

Set proper offset value to trim ADC.

To minimize the offset during normal operation, software should read the conversion result from the RESFIFO calibration operation and write the lower 6 bits to the OFSTRIM register.

Parameters

- base – LPADC peripheral base address.
- value – Setting offset value.

status_t LPADC_DoAutoCalibration(ADC_Type *base)

Do auto calibration.

Calibration function should be executed before using converter in application. It used the software trigger and a dummy conversion, get the offset and write them into the OFSTRIM register. It called some of functional API including:

- LPADC_EnableCalibration(...)
- LPADC_SetOffsetValue(...)

- LPADC_SetConvCommandConfig(...)
- LPADC_SetConvTriggerConfig(...)

Parameters

- base – LPADC peripheral base address.
- base – LPADC peripheral base address.

Return values

- kStatus_Success – Successfully configured.
- kStatus_Timeout – Timeout occurs while waiting completion.

static inline void LPADC_SetOffsetValue(ADC_Type *base, int16_t value)

Set trim value for offset.

Note: For 16-bit conversions, each increment is 1/2 LSB resulting in a programmable offset range of -256 LSB to 255.5 LSB; For 12-bit conversions, each increment is 1/32 LSB resulting in a programmable offset range of -16 LSB to 15.96875 LSB.

Parameters

- base – LPADC peripheral base address.
- value – Offset trim value, is a 10-bit signed value between -512 and 511.

static inline void LPADC_GetOffsetValue(ADC_Type *base, int16_t *pValue)

Get trim value of offset.

Parameters

- base – LPADC peripheral base address.
- pValue – Pointer to the variable in type of int16_t to store offset value.

static inline void LPADC_EnableOffsetCalibration(ADC_Type *base, bool enable)

Enable the offset calibration function.

Parameters

- base – LPADC peripheral base address.
- enable – switcher to the calibration function.

static inline void LPADC_SetOffsetCalibrationMode(ADC_Type *base, *lpadc_offset_calibration_mode_t* mode)

Set offset calibration mode.

Parameters

- base – LPADC peripheral base address.
- mode – set offset calibration mode.see to *lpadc_offset_calibration_mode_t* .

status_t LPADC_DoOffsetCalibration(ADC_Type *base)

Do offset calibration.

Parameters

- base – LPADC peripheral base address.

Return values

- kStatus_Success – Successfully configured.

- kStatus_Timeout – Timeout occurs while waiting completion.

void LPADC_PrepareAutoCalibration(ADC_Type *base)

Prepare auto calibration, LPADC_FinishAutoCalibration has to be called before using the LPADC. LPADC_DoAutoCalibration has been split in two API to avoid to be stuck too long in the function.

Parameters

- base – LPADC peripheral base address.

status_t LPADC_FinishAutoCalibration(ADC_Type *base)

Finish auto calibration start with LPADC_PrepareAutoCalibration.

Note: This feature is used for LPADC with CTRL[CALOFSMODE].

Parameters

- base – LPADC peripheral base address.

Return values

- kStatus_Success – Successfully configured.
- kStatus_Timeout – Timeout occurs while waiting completion.

void LPADC_GetCalibrationValue(ADC_Type *base, *lpadc_calibration_value_t* *ptrCalibrationValue)

Get calibration value into the memory which is defined by invoker.

Note: Please note the ADC will be disabled temporary.

Note: This function should be used after finish calibration.

Parameters

- base – LPADC peripheral base address.
- ptrCalibrationValue – Pointer to *lpadc_calibration_value_t* structure, this memory block should be always powered on even in low power modes.

status_t LPADC_SetCalibrationValue(ADC_Type *base, const *lpadc_calibration_value_t* *ptrCalibrationValue)

Set calibration value into ADC calibration registers.

Note: Please note the ADC will be disabled temporary.

Parameters

- base – LPADC peripheral base address.
- ptrCalibrationValue – Pointer to *lpadc_calibration_value_t* structure which contains ADC's calibration value.

Return values

- kStatus_Success – Successfully configured.

- kStatus_Timeout – Timeout occurs while waiting completion.

static inline void LPADC_RequestHighSpeedModeTrim(ADC_Type *base)

Request high speed mode trim calculation.

Parameters

- base – LPADC peripheral base address.

static inline int8_t LPADC_GetHighSpeedTrimValue(ADC_Type *base)

Get high speed mode trim value, the result is a 5-bit signed value between -16 and 15.

Note: The high speed mode trim value is used to minimize offset for high speed conversion.

Parameters

- base – LPADC peripheral base address.

Returns

The calculated high speed mode trim value.

static inline void LPADC_SetHighSpeedTrimValue(ADC_Type *base, int8_t trimValue)

Set high speed mode trim value.

Note: If is possible to set the trim value manually, but it is recommended to use the LPADC_RequestHighSpeedModeTrim.

Parameters

- base – LPADC peripheral base address.
- trimValue – The trim value to be set.

static inline void LPADC_EnableHighSpeedConversionMode(ADC_Type *base, bool enable)

Enable/disable high speed conversion mode, if enabled conversions complete 2 or 3 ADCK cycles sooner compared to conversion cycle counts when high speed mode is disabled.

Parameters

- base – LPADC peripheral base address.
- enable – Used to enable/disable high speed conversion mode:
  - **true** Enable high speed conversion mode;
  - **false** Disable high speed conversion mode.

static inline void LPADC_EnableExtraCycle(ADC_Type *base, bool enable)

Enable/disable an additional ADCK cycle to conversion.

Parameters

- base – LPADC peripheral base address.
- enable – Used to enable/disable an additional ADCK cycle to conversion:
  - **true** Enable an additional ADCK cycle to conversion;
  - **false** Disable an additional ADCK cycle to conversion.

static inline void LPADC_SetTuneValue(ADC_Type *base, *lpadc_tune_value_t* tuneValue)

Set tune value which provides some variability in how many cycles are needed to complete a conversion.

Parameters

- base – LPADC peripheral base address.
- tuneValue – The tune value to be set, please refer to *lpadc_tune_value_t*.

static inline *lpadc_tune_value_t* LPADC_GetTuneValue(ADC_Type *base)

Get tune value which provides some variability in how many cycles are needed to complete a conversion.

Parameters

- base – LPADC peripheral base address.

Returns

The tune value, please refer to *lpadc_tune_value_t*.

static inline void LPADC_EnableJustifiedLeft(ADC_Type *base, bool enable)

Enable/disable left-justify format in 12-bit single-end mode.

Parameters

- base – LPADC peripheral base address.
- enable – Used to enable/disable left-justify format in 12-bit single-end mode:
  - **true** Enable left-justify format in 12-bit single-end mode;
  - **false** Disable left-justify format in 12-bit single-end mode.

FSL_LPADC_DRIVER_VERSION

LPADC driver version 2.10.3.

struct lpadc_config_t

#include <fsl_lpadc.h> LPADC global configuration.

This structure would used to keep the settings for initialization.

Public Members

bool enableInternalClock

Enables the internally generated clock source. The clock source is used in clock selection logic at the chip level and is optionally used for the ADC clock source.

bool enableVref1LowVoltage

If voltage reference option1 input is below 1.8V, it should be “true”. If voltage reference option1 input is above 1.8V, it should be “false”.

bool enableInDozeMode

Control system transition to Stop and Wait power modes while ADC is converting. When enabled in Doze mode, immediate entries to Wait or Stop are allowed. When disabled, the ADC will wait for the current averaging iteration/FIFO storage to complete before acknowledging stop or wait mode entry.

lpadc_conversion_average_mode_t conversionAverageMode

Auto-Calibration Averages.

bool enableAnalogPreliminary

ADC analog circuits are pre-enabled and ready to execute conversions without startup delays(at the cost of higher DC current consumption).

uint32_t powerUpDelay

When the analog circuits are not pre-enabled, the ADC analog circuits are only powered while the ADC is active and there is a counted delay defined by this field after an initial trigger transitions the ADC from its Idle state to allow time for the analog circuits to stabilize. The startup delay count of (powerUpDelay * 4) ADCK cycles must result in a longer delay than the analog startup time.

lpadc_reference_voltage_source_t referenceVoltageSource

Selects the voltage reference high used for conversions.

lpadc_power_level_mode_t powerLevelMode

Power Configuration Selection.

lpadc_trigger_priority_policy_t triggerPriorityPolicy

Control how higher priority triggers are handled, see to lpadc_trigger_priority_policy_t.

bool enableConvPause

Enables the ADC pausing function. When enabled, a programmable delay is inserted during command execution sequencing between LOOP iterations, between commands in a sequence, and between conversions when command is executing in “Compare Until True” configuration.

uint32_t convPauseDelay

Controls the duration of pausing during command execution sequencing. The pause delay is a count of (convPauseDelay*4) ADCK cycles. Only available when ADC pausing function is enabled. The available value range is in 9-bit.

uint32_t FIFOWatermark

FIFOWatermark is a programmable threshold setting. When the number of datawords stored in the ADC Result FIFO is greater than the value in this field, the ready flag would be asserted to indicate stored data has reached the programmable threshold.

struct lpadc_conv_command_config_t

#include <fsl_lpadc.h> Define structure to keep the configuration for conversion command.

Public Members

lpadc_sample_scale_mode_t sampleScaleMode

Sample scale mode.

lpadc_sample_scale_mode_t channelBScaleMode

Alternate channe B Scale mode.

lpadc_sample_channel_mode_t sampleChannelMode

Channel sample mode.

uint32_t channelNumber

Channel number, select the channel or channel pair.

uint32_t channelBNumber

Alternate Channel B number, select the channel.

uint32_t chainedNextCommandNumber

Selects the next command to be executed after this command completes. 1-15 is available, 0 is to terminate the chain after this command.

bool enableAutoChannelIncrement

Loop with increment: when disabled, the "loopCount" field selects the number of times the selected channel is converted consecutively; when enabled, the "loopCount" field defines how many consecutive channels are converted as part of the command execution.

uint32_t loopCount

Selects how many times this command executes before finish and transition to the next command or Idle state. Command executes LOOP+1 times. 0-15 is available.

lpadc_hardware_average_mode_t hardwareAverageMode

Hardware average selection.

lpadc_sample_time_mode_t sampleTimeMode

Sample time selection.

lpadc_hardware_compare_mode_t hardwareCompareMode

Hardware compare selection.

uint32_t hardwareCompareValueHigh

Compare Value High. The available value range is in 16-bit.

uint32_t hardwareCompareValueLow

Compare Value Low. The available value range is in 16-bit.

lpadc_conversion_resolution_mode_t conversionResolutionMode

Conversion resolution mode.

bool enableWaitTrigger

Wait for trigger assertion before execution: when disabled, this command will be automatically executed; when enabled, the active trigger must be asserted again before executing this command.

struct lpadc_conv_trigger_config_t

#include <fsl_lpadc.h> Define structure to keep the configuration for conversion trigger.

Public Members

uint32_t targetCommandId

Select the command from command buffer to execute upon detect of the associated trigger event.

uint32_t delayPower

Select the trigger delay duration to wait at the start of servicing a trigger event. When this field is clear, then no delay is incurred. When this field is set to a non-zero value, the duration for the delay is 2^delayPower ADCK cycles. The available value range is 4-bit.

uint32_t priority

Sets the priority of the associated trigger source. If two or more triggers have the same priority level setting, the lower order trigger event has the higher priority. The lower value for this field is for the higher priority, the available value range is 1-bit.

bool enableHardwareTrigger

Enable hardware trigger source to initiate conversion on the rising edge of the input trigger source or not. THe software trigger is always available.

struct lpadc_conv_result_t

#include <fsl_lpadc.h> Define the structure to keep the conversion result.

Public Members

uint32_t commandIdSource

Indicate the command buffer being executed that generated this result.

uint32_t loopCountIndex

Indicate the loop count value during command execution that generated this result.

uint32_t triggerIdSource

Indicate the trigger source that initiated a conversion and generated this result.

uint16_t convValue

Data result.

struct __lpadc_calibration_value

#include <fsl_lpadc.h> A structure of calibration value.

2.47 Lpc_freqme

void FREQME_Init(FREQME_Type *base, const *freq_measure_config_t* *config)

Initialize freqme module, set operate mode, operate mode attribute and initialize measurement cycle.

Parameters

- base – FREQME peripheral base address.
- config – The pointer to module basic configuration, please refer to *freq_measure_config_t*.

void FREQME_GetDefaultConfig(*freq_measure_config_t* *config)

Get default configuration.

```
config->operateMode = kFREQME_FreqMeasurementMode;
config->operateModeAttribute.refClkScaleFactor = 0U;
config->enableContinuousMode                   = false;
config->startMeasurement                       = false;
```

Parameters

- config – The pointer to module basic configuration, please refer to *freq_measure_config_t*.

static inline void FREQME_StartMeasurementCycle(FREQME_Type *base)

Start frequency or pulse width measurement process.

Parameters

- base – FREQME peripheral base address.

static inline void FREQME_TerminateMeasurementCycle(FREQME_Type *base)

Force the termination of any measurement cycle currently in progress and resets RESULT or just reset RESULT if the module in idle state.

Parameters

- base – FREQME peripheral base address.

static inline void FREQME_EnableContinuousMode(FREQME_Type *base, bool enable)

Enable/disable Continuous mode.

Parameters

- base – FREQME peripheral base address.
- enable – Used to enable/disable continuous mode,
  - **true** Enable Continuous mode.
  - **false** Disable Continuous mode.

static inline bool FREQME_CheckContinuousMode(FREQME_Type *base)

Check whether continuous mode is enabled.

Parameters

- base – FREQME peripheral base address.

Return values

- True – Continuous mode is enabled, the measurement is performed continuously.
- False – Continuous mode is disabled.

static inline void FREQME_SetOperateMode(FREQME_Type *base, *freqme_operate_mode_t* operateMode)

Set operate mode of freqme module.

Parameters

- base – FREQME peripheral base address.

- operateMode – The operate mode to be set, please refer to *freqme_operate_mode_t*.

static inline bool FREQME_CheckOperateMode(FREQME_Type *base)

Check module's operate mode.

Parameters

- base – FREQME peripheral base address.

Return values

- True – Pulse width measurement mode.
- False – Frequency measurement mode.

static inline void FREQME_SetMinExpectedValue(FREQME_Type *base, uint32_t minValue)

Set the minimum expected value for the measurement result.

Parameters

- base – FREQME peripheral base address.
- minValue – The minimum value to set, please note that this value is 31 bits width.

static inline void FREQME_SetMaxExpectedValue(FREQME_Type *base, uint32_t maxValue)

Set the maximum expected value for the measurement result.

Parameters

- base – FREQME peripheral base address.
- maxValue – The maximum value to set, please note that this value is 31 bits width.

static inline void FREQME_SetReferenceClk(FREQME_Type *base, uint32_t referenceClk)

Set the reference clock source.

Parameters

- base – FREQME peripheral base address.
- referenceClk – The reference clock source, see freqme_reference_clock_t in <device>_COMMON.h.

static inline void FREQME_SetTargetClk(FREQME_Type *base, uint32_t targetClk)

Set the target clock source.

Parameters

- base – FREQME peripheral base address.
- targetClk – The target clock source, see freqme_target_clock_t in <device>_COMMON.h.

uint32_t FREQME_CalculateTargetClkFreq(FREQME_Type *base, uint32_t refClkFrequency)

Calculate the frequency of selected target clock.

Note: The formula: Ftarget = (RESULT - 2) * Freference / 2 ^ REF_SCALE or Ftarget = (RESULT + 1) * Freference / 2 ^ REF_SCALE

Note: This function only useful when the operate mode is selected as frequency measurement mode.

Parameters

- base – FREQME peripheral base address.
- refClkFrequency – The frequency of reference clock.

Returns

The frequency of target clock, if the output result is 0, please check the module's operate mode.

static inline uint8_t FREQME_GetReferenceClkScaleValue(FREQME_Type *base)

Get reference clock scaling factor.

Parameters

- base – FREQME peripheral base address.

Returns

Reference clock scaling factor, the reference count cycle is 2 ^ ref_scale.

static inline void FREQME_SetPulsePolarity(FREQME_Type *base, *freqme_pulse_polarity_t* pulsePolarity)

Set pulse polarity when operate mode is selected as Pulse Width Measurement mode.

Parameters

- base – FREQME peripheral base address.
- pulsePolarity – The pulse polarity to be set, please refer to *freqme_pulse_polarity_t*.

static inline bool FREQME_CheckPulsePolarity(FREQME_Type *base)

Check pulse polarity when the operate mode is selected as pulse width measurement mode.

Parameters

- base – FREQME peripheral base address.

Return values

- True – Low period.
- False – High period.

static inline uint32_t FREQME_GetMeasurementResult(FREQME_Type *base)

Get measurement result.

Parameters

- base – FREQME peripheral base address.

Returns

Measurement result.

static inline uint32_t FREQME_GetInterruptStatusFlags(FREQME_Type *base)

Get interrupt status flags, such as overflow interrupt status flag, underflow interrupt status flag, and so on.

Parameters

- base – FREQME peripheral base address.

Returns

Current interrupt status flags, should be the OR'ed value of *_freqme_interrupt_status_flags*.

static inline void FREQME_ClearInterruptStatusFlags(FREQME_Type *base, uint32_t statusFlags)

Clear interrupt status flags.

Parameters

- base – FREQME peripheral base address.
- statusFlags – The combination of interrupt status flags to clear, should be the OR'ed value of *_freqme_interrupt_status_flags*.

static inline void FREQME_EnableInterrupts(FREQME_Type *base, uint32_t masks)

Enable interrupts, such as result ready interrupt, overflow interrupt and so on.

Parameters

- base – FREQME peripheral base address.
- masks – The mask of interrupts to enable, should be the OR'ed value of *_freqme_interrupt_enable*.

static inline void FREQME_DisableInterrupts(FREQME_Type *base, uint32_t masks)

Disable interrupts, such as result ready interrupt, overflow interrupt and so on.

Parameters

- base – FREQME peripheral base address.
- masks – The mask of interrupts to disable, should be the OR'ed value of *_freqme_interrupt_enable*.

FSL_FREQME_DRIVER_VERSION

FREQME driver version 2.2.0.

enum _freqme_interrupt_status_flags

The enumeration of interrupt status flags. .

Values:

enumerator kFREQME_UnderflowInterruptStatusFlag

Indicate the measurement is just done and the result is less than minimum value.

enumerator kFREQME_OverflowInterruptStatusFlag

Indicate the measurement is just done and the result is greater than maximum value.

enumerator kFREQME_ReadyInterruptStatusFlag

Indicate the measurement is just done and the result is ready to read.

enumerator kFREQME_AllInterruptStatusFlags

All interrupt status flags.

enum _freqme_interrupt_enable

The enumeration of interrupts, including underflow interrupt, overflow interrupt, and result ready interrupt. .

Values:

enumerator kFREQME_UnderflowInterruptEnable

Enable interrupt when the result is less than minimum value.

enumerator kFREQME_OverflowInterruptEnable

Enable interrupt when the result is greater than maximum value.

enumerator kFREQME_ReadyInterruptEnable

Enable interrupt when a measurement completes and the result is ready.

enum _freqme_operate_mode

FREQME module operate mode enumeration, including frequency measurement mode and pulse width measurement mode.

Values:

enumerator kFREQME_FreqMeasurementMode

The module works in the frequency measurement mode.

enumerator kFREOME_PulseWidthMeasurementMode

The module works in the pulse width measurement mode.

enum _freqme_pulse_polarity

The enumeration of pulse polarity.

Values:

enumerator kFREQME_PulseHighPeriod

Select high period of the reference clock.

enumerator kFREQME_PulseLowPeriod

Select low period of the reference clock.

typedef enum *_freqme_operate_mode* freqme_operate_mode_t

FREQME module operate mode enumeration, including frequency measurement mode and pulse width measurement mode.

typedef enum *_freqme_pulse_polarity* freqme_pulse_polarity_t

The enumeration of pulse polarity.

typedef union *_freqme_mode_attribute* freqme_mode_attribute_t

The union of operate mode attribute.

Note: If the operate mode is selected as frequency measurement mode the member **refClkScaleFactor** should be used, if the operate mode is selected as pulse width measurement mode the member **pulsePolarity** should be used.

---

typedef struct *_freq_measure_config* freq_measure_config_t

The structure of freqme module basic configuration, including operate mode, operate mode attribute and so on.

union _freqme_mode_attribute

#include <fsl_freqme.h> The union of operate mode attribute.

Note: If the operate mode is selected as frequency measurement mode the member **refClkScaleFactor** should be used, if the operate mode is selected as pulse width measurement mode the member **pulsePolarity** should be used.

Public Members

uint8_t refClkScaleFactor

Only useful in frequency measurement operate mode, used to set the reference clock counter scaling factor.

freqme_pulse_polarity_t pulsePolarity

Only Useful in pulse width measurement operate mode, used to set period polarity.

struct __freq__measure__config

#include <fsl_freqme.h> The structure of freqme module basic configuration, including operate mode, operate mode attribute and so on.

Public Members

freqme_operate_mode_t operateMode

Select operate mode, please refer to *freqme_operate_mode_t*.

freqme_mode_attribute_t operateModeAttribute

Used to set the attribute of the selected operate mode, if the operate mode is selected as *kFREQME_FreqMeasurementMode* set *freqme_mode_attribute_t::refClkScaleFactor*, if operate mode is selected as *kFREOME_PulseWidthMeasurementMode*, please set *freqme_mode_attribute_t::pulsePolarity*.

bool enableContinuousMode

Enable/disable continuous mode, if continuous mode is enable, the measurement is performed continuously and the result for the last completed measurement is available in the result register.

2.48 LPCMP: Low Power Analog Comparator Driver

void LPCMP_Init(LPCMP_Type *base, const *lpcmp_config_t* *config)

Initialize the LPCMP.

This function initializes the LPCMP module. The operations included are:

- Enabling the clock for LPCMP module.
- Configuring the comparator.
- Enabling the LPCMP module. Note: For some devices, multiple LPCMP instance share the same clock gate. In this case, to enable the clock for any instance enables all the LPCMPs. Check the chip reference manual for the clock assignment of the LPCMP.

Parameters

- base – LPCMP peripheral base address.
- config – Pointer to "lpcmp_config_t" structure.

void LPCMP_Deinit(LPCMP_Type *base)

De-initializes the LPCMP module.

This function de-initializes the LPCMP module. The operations included are:

- Disabling the LPCMP module.
- Disabling the clock for LPCMP module.

This function disables the clock for the LPCMP. Note: For some devices, multiple LPCMP instance shares the same clock gate. In this case, before disabling the clock for the LPCMP, ensure that all the LPCMP instances are not used.

Parameters

- base – LPCMP peripheral base address.

void LPCMP_GetDefaultConfig(*lpcmp_config_t* *config)

Gets an available pre-defined settings for the comparator's configuration.

This function initializes the comparator configuration structure to these default values:

```
config->enableStopMode      = false;
config->enableOutputPin     = false;
config->enableCmpToDacLink  = false;
config->useUnfilteredOutput = false;
config->enableInvertOutput  = false;
config->hysteresisMode      = kLPCMP_HysteresisLevel0;
config->powerMode           = kLPCMP_LowSpeedPowerMode;
config->functionalSourceClock = kLPCMP_FunctionalClockSource0;
config->plusInputSrc        = kLPCMP_PlusInputSrcMux;
config->minusInputSrc       = kLPCMP_MinusInputSrcMux;
```

Parameters

- config – Pointer to "lpcmp_config_t" structure.

static inline void LPCMP_Enable(LPCMP_Type *base, bool enable)

Enable/Disable LPCMP module.

Parameters

- base – LPCMP peripheral base address.
- enable – "true" means enable the module, and "false" means disable the module.

void LPCMP_SetInputChannels(LPCMP_Type *base, uint32_t positiveChannel, uint32_t negativeChannel)

Select the input channels for LPCMP. This function determines which input is selected for the negative and positive mux.

Parameters

- base – LPCMP peripheral base address.
- positiveChannel – Positive side input channel number. Available range is 0-7.
- negativeChannel – Negative side input channel number. Available range is 0-7.

static inline void LPCMP_EnableDMA(LPCMP_Type *base, bool enable)

Enables/disables the DMA request for rising/falling events. Normally, the LPCMP generates a CPU interrupt if there is a rising/falling event. When DMA support is enabled and the rising/falling interrupt is enabled , the rising/falling event forces a DMA transfer request rather than a CPU interrupt instead.

Parameters

- base – LPCMP peripheral base address.
- enable – "true" means enable DMA support, and "false" means disable DMA support.

void LPCMP_SetFilterConfig(LPCMP_Type *base, const *lpcmp_filter_config_t* *config)

Configures the filter.

Parameters

- base – LPCMP peripheral base address.
- config – Pointer to "lpcmp_filter_config_t" structure.

void LPCMP_SetDACConfig(LPCMP_Type *base, const *lpcmp_dac_config_t* *config)

Configure the internal DAC module.

Parameters

- base – LPCMP peripheral base address.
- config – Pointer to "lpcmp_dac_config_t" structure. If config is "NULL", disable internal DAC.

static inline void LPCMP_EnableInterrupts(LPCMP_Type *base, uint32_t mask)

Enable the interrupts.

Parameters

- base – LPCMP peripheral base address.
- mask – Mask value for interrupts. See "_lpcmp_interrupt_enable".

static inline void LPCMP_DisableInterrupts(LPCMP_Type *base, uint32_t mask)

Disable the interrupts.

Parameters

- base – LPCMP peripheral base address.
- mask – Mask value for interrupts. See "_lpcmp_interrupt_enable".

static inline uint32_t LPCMP_GetStatusFlags(LPCMP_Type *base)

Get the LPCMP status flags.

Parameters

- base – LPCMP peripheral base address.

Returns

Mask value for the asserted flags. See "_lpcmp_status_flags".

static inline void LPCMP_ClearStatusFlags(LPCMP_Type *base, uint32_t mask)

Clear the LPCMP status flags.

Parameters

- base – LPCMP peripheral base address.
- mask – Mask value for the flags. See "_lpcmp_status_flags".

static inline void LPCMP_EnableWindowMode(LPCMP_Type *base, bool enable)

Enable/Disable window mode.When any windowed mode is active, COUTA is clocked by the bus clock whenever WINDOW = 1. The last latched value is held when WINDOW = 0. The optionally inverted comparator output COUT_RAW is sampled on every bus clock when WINDOW=1 to generate COUTA.

Parameters

- base – LPCMP peripheral base address.
- enable – "true" means enable window mode, and "false" means disable window mode.

void LPCMP_SetWindowControl(LPCMP_Type *base, const *lpcmp_window_control_config_t* *config)

Configure the window control, users can use this API to implement operations on the window, such as inverting the window signal, setting the window closing event(only valid in windowing mode), and setting the COUTA signal after the window is closed(only valid in windowing mode).

Parameters

- base – LPCMP peripheral base address.
- config – Pointer "lpcmp_window_control_config_t" structure.

void LPCMP_SetRoundRobinConfig(LPCMP_Type *base, const *lpcmp_roundrobin_config_t* *config)

Configure the roundrobin mode.

Parameters

- base – LPCMP peripheral base address.
- config – Pointer "lpcmp_roundrobin_config_t" structure.

static inline void LPCMP_EnableRoundRobinMode(LPCMP_Type *base, bool enable)

Enable/Disable roundrobin mode.

Parameters

- base – LPCMP peripheral base address.
- enable – "true" means enable roundrobin mode, and "false" means disable roundrobin mode.

void LPCMP_SetRoundRobinInternalTimer(LPCMP_Type *base, uint32_t value)

brief Configure the roundrobin internal timer reload value.

param base LPCMP peripheral base address. param value RoundRobin internal timer reload value, allowed range:0x0UL-0xFFFFFFFUL.

static inline void LPCMP_EnableRoundRobinInternalTimer(LPCMP_Type *base, bool enable)

Enable/Disable roundrobin internal timer, note that this function is only valid when using the internal trigger source.

Parameters

- base – LPCMP peripheral base address.
- enable – "true" means enable roundrobin internal timer, and "false" means disable roundrobin internal timer.

static inline void LPCMP_SetPreSetValue(LPCMP_Type *base, uint8_t mask)

Set preset value for all channels, users can set all channels' preset vaule through this API, for example, if the mask set to 0x03U means channel0 and channel2's preset value set to 1U and other channels' preset value set to 0U.

Parameters

- base – LPCMP peripheral base address.
- mask – Mask of channel index.

static inline uint8_t LPCMP_GetComparisonResult(LPCMP_Type *base)

Get comparison results for all channels, users can get all channels' comparison results through this API.

Parameters

- base – LPCMP peripheral base address.

Returns

return All channels' comparison result.

static inline void LPCMP_ClearInputChangedFlags(LPCMP_Type *base, uint8_t mask)

Clear input changed flags for single channel or multiple channels, users can clear input changed flag of a single channel or multiple channels through this API, for example, if the mask set to 0x03U means clear channel0 and channel2's input changed flags.

Parameters

- base – LPCMP peripheral base address.
- mask – Mask of channel index.

static inline uint8_t LPCMP_GetInputChangedFlags(LPCMP_Type *base)

Get input changed flags for all channels, Users can get all channels' input changed flags through this API.

Parameters

- base – LPCMP peripheral base address.

Returns

return All channels' changed flag.

FSL_LPCMP_DRIVER_VERSION

LPCMP driver version 2.3.2.

enum _lpcmp_status_flags

LPCMP status falgs mask.

Values:

enumerator kLPCMP_OutputRisingEventFlag

Rising-edge on the comparison output has occurred.

enumerator kLPCMP_OutputFallingEventFlag

Falling-edge on the comparison output has occurred.

enumerator kLPCMP_OutputRoundRobinEventFlag

Detects when any channel's last comparison result is different from the pre-set value in trigger mode.

enumerator kLPCMP_OutputAssertEventFlag

Return the current value of the analog comparator output. The flag does not support W1C.

enum _lpcmp_interrupt_enable

LPCMP interrupt enable/disable mask.

Values:

enumerator kLPCMP_OutputRisingInterruptEnable

Comparator interrupt enable rising.

enumerator kLPCMP_OutputFallingInterruptEnable

Comparator interrupt enable falling.

enumerator kLPCMP_RoundRobinInterruptEnable

Comparator round robin mode interrupt occurred when the comparison result changes for a given channel.

enum _lpcmp_hysteresis_mode

LPCMP hysteresis mode. See chip data sheet to get the actual hystersis value with each level.

Values:

enumerator kLPCMP_HysteresisLevel0

The hard block output has level 0 hysteresis internally.

enumerator kLPCMP_HysteresisLevel1

The hard block output has level 1 hysteresis internally.

enumerator kLPCMP_HysteresisLevel2

The hard block output has level 2 hysteresis internally.

enumerator kLPCMP_HysteresisLevel3

The hard block output has level 3 hysteresis internally.

enum _lpcmp_power_mode

LPCMP nano mode.

Values:

enumerator kLPCMP_LowSpeedPowerMode

Low speed comparison mode is selected.

enumerator kLPCMP_HighSpeedPowerMode

High speed comparison mode is selected.

enumerator kLPCMP_NanoPowerMode

Nano power comparator is enabled.

enum _lpcmp_dac_reference_voltage_source

Internal DAC reference voltage source.

Values:

enumerator kLPCMP_VrefSourceVin1

vrefh_int is selected as resistor ladder network supply reference Vin.

enumerator kLPCMP_VrefSourceVin2

vrefh_ext is selected as resistor ladder network supply reference Vin.

enum _lpcmp_functional_source_clock

LPCMP functional mode clock source selection.

Note: In different devices, the functional mode clock source selection is different, please refer to specific device Reference Manual for details.

Values:

enumerator kLPCMP_FunctionalClockSource0

Select functional mode clock source0.

enumerator kLPCMP_FunctionalClockSource1

Select functional mode clock source1.

enumerator kLPCMP_FunctionalClockSource2

Select functional mode clock source2.

enumerator kLPCMP_FunctionalClockSource3

Select functional mode clock source3.

enum _lpcmp_couta_signal

Set the COUTA signal value when the window is closed.

Values:

enumerator kLPCMP_COUTASignalNoSet

NO set the COUTA signal value when the window is closed.

enumerator kLPCMP_COUTASignalLow

Set COUTA signal low(0) when the window is closed.

enumerator kLPCMP_COUTASignalHigh

Set COUTA signal high(1) when the window is closed.

enum _lpcmp_close_window_event

Set COUT event, which can close the active window in window mode.

Values:

enumerator kLPCMP_CLoseWindowEventNoSet

No Set COUT event, which can close the active window in window mode.

enumerator kLPCMP_CloseWindowEventRisingEdge

Set rising edge COUT signal as COUT event.

enumerator kLPCMP_CloseWindowEventFallingEdge
Set falling edge COUT signal as COUT event.

enumerator kLPCMP_CLoseWindowEventBothEdge
Set both rising and falling edge COUT signal as COUT event.

enum _lpcmp_roundrobin_fixedmuxport
LPCMP round robin mode fixed mux port.
Values:

enumerator kLPCMP_FixedPlusMuxPort
Fixed plus mux port.

enumerator kLPCMP_FixedMinusMuxPort
Fixed minus mux port.

enum _lpcmp_roundrobin_clock_source
LPCMP round robin mode clock source selection.
Note: In different devices,the round robin mode clock source selection is different, please refer to the specific device Reference Manual for details.
Values:

enumerator kLPCMP_RoundRobinClockSource0
Select roundrobin mode clock source0.

enumerator kLPCMP_RoundRobinClockSource1
Select roundrobin mode clock source1.

enumerator kLPCMP_RoundRobinClockSource2
Select roundrobin mode clock source2.

enumerator kLPCMP_RoundRobinClockSource3
Select roundrobin mode clock source3.

enum _lpcmp_roundrobin_trigger_source
LPCMP round robin mode trigger source.
Values:

enumerator kLPCMP_TriggerSourceExternally
Select external trigger source.

enumerator kLPCMP_TriggerSourceInternally
Select internal trigger source.

enum _lpcmp_plus_input_src
LPCMP plus input source.
Values:

enumerator kLPCMP_PlusInputSrcDac

LPCMP plus input source from the internal 8-bit DAC output.

enumerator kLPCMP_PlusInputSrcMux

LPCMP plus input source from the analog 8-1 mux.

enum _lpcmp_minus_input_src

LPCMP minus input source.

Values:

enumerator kLPCMP_MinusInputSrcDac

LPCMP minus input source from the internal 8-bit DAC output.

enumerator kLPCMP_MinusInputSrcMux

LPCMP minus input source from the analog 8-1 mux.

typedef enum *_lpcmp_hysteresis_mode* lpcmp_hysteresis_mode_t

LPCMP hysteresis mode. See chip data sheet to get the actual hystersis value with each level.

typedef enum *_lpcmp_power_mode* lpcmp_power_mode_t

LPCMP nano mode.

typedef enum *_lpcmp_dac_reference_voltage_source* lpcmp_dac_reference_voltage_source_t

Internal DAC reference voltage source.

typedef enum *_lpcmp_functional_source_clock* lpcmp_functional_source_clock_t

LPCMP functional mode clock source selection.

Note: In different devices, the functional mode clock source selection is different, please refer to specific device Reference Manual for details.

typedef enum *_lpcmp_couta_signal* lpcmp_couta_signal_t

Set the COUTA signal value when the window is closed.

typedef enum *_lpcmp_close_window_event* lpcmp_close_window_event_t

Set COUT event, which can close the active window in window mode.

typedef enum *_lpcmp_roundrobin_fixedmuxport* lpcmp_roundrobin_fixedmuxport_t

LPCMP round robin mode fixed mux port.

typedef enum *_lpcmp_roundrobin_clock_source* lpcmp_roundrobin_clock_source_t

LPCMP round robin mode clock source selection.

Note: In different devices,the round robin mode clock source selection is different, please refer to the specific device Reference Manual for details.

typedef enum *_lpcmp_roundrobin_trigger_source* lpcmp_roundrobin_trigger_source_t

LPCMP round robin mode trigger source.

typedef struct *_lpcmp_filter_config* lpcmp_filter_config_t
Configure the filter.

typedef enum *_lpcmp_plus_input_src* lpcmp_plus_input_src_t
LPCMP plus input source.

typedef enum *_lpcmp_minus_input_src* lpcmp_minus_input_src_t
LPCMP minus input source.

typedef struct *_lpcmp_dac_config* lpcmp_dac_config_t
configure the internal DAC.

typedef struct *_lpcmp_config* lpcmp_config_t
Configures the comparator.

typedef struct *_lpcmp_window_control_config* lpcmp_window_control_config_t
Configure the window mode control.

typedef struct *_lpcmp_roundrobin_config* lpcmp_roundrobin_config_t
Configure the round robin mode.

LPCMP_CCR1_COUTA_CFG_MASK

LPCMP_CCR1_COUTA_CFG_SHIFT

LPCMP_CCR1_COUTA_CFG(x)

LPCMP_CCR1_EVT_SEL_CFG_MASK

LPCMP_CCR1_EVT_SEL_CFG_SHIFT

LPCMP_CCR1_EVT_SEL_CFG(x)

struct _lpcmp_filter_config
#include <fsl_lpcmp.h> Configure the filter.

Public Members

bool enableSample
Decide whether to use the external SAMPLE as a sampling clock input.

uint8_t filterSampleCount
Filter Sample Count. Available range is 1-7; 0 disables the filter.

uint8_t filterSamplePeriod
Filter Sample Period. The divider to the bus clock. Available range is 0-255. The sampling clock must be at least 4 times slower than the system clock to the comparator. So if enableSample is “false”, filterSamplePeriod should be set greater than 4.

struct _lpcmp_dac_config

#include <fsl_lpcmp.h> configure the internal DAC.

Public Members

bool enableLowPowerMode

Decide whether to enable DAC low power mode.

lpcmp_dac_reference_voltage_source_t referenceVoltageSource

Internal DAC supply voltage reference source.

uint8_t DACValue

Value for the DAC Output Voltage. Different devices has different available range, for specific values, please refer to the reference manual.

struct _lpcmp_config

#include <fsl_lpcmp.h> Configures the comparator.

Public Members

bool enableStopMode

Decide whether to enable the comparator when in STOP modes.

bool enableCmpToDacLink

Controls the link from the CMP enable to the DAC enable.

bool enableOutputPin

Decide whether to enable the comparator is available in selected pin.

bool useUnfilteredOutput

Decide whether to use unfiltered output.

bool enableInvertOutput

Decide whether to inverts the comparator output.

lpcmp_hysteresis_mode_t hysteresisMode

LPCMP hysteresis mode.

lpcmp_power_mode_t powerMode

LPCMP power mode.

lpcmp_functional_source_clock_t functionalSourceClock

Select LPCMP functional mode clock source.

lpcmp_plus_input_src_t plusInputSrc

Select LPCMP plus input source.

lpcmp_minus_input_src_t minusInputSrc

Select LPCMP minus input source.

struct _lpcmp_window_control_config

#include <fsl_lpcmp.h> Configure the window mode control.

Public Members

bool enableInvertWindowSignal

True: enable invert window signal, False: disable invert window signal.

lpcmp_couta_signal_t COUTASignal

Decide whether to define the COUTA signal value when the window is closed.

lpcmp_close_window_event_t closeWindowEvent

Decide whether to select COUT event signal edge defines a COUT event to close window.

struct _lpcmp_roundrobin_config

#include <fsl_lpcmp.h> Configure the round robin mode.

Public Members

uint8_t initDelayModules

Comparator and DAC initialization delay modulus, See Reference Manual and DataSheet for specific value.

uint8_t sampleClockNumbers

Specify the number of the round robin clock cycles(0~3) to wait after scanning the active channel before sampling the channel's comparison result.

uint8_t channelSampleNumbers

Specify the number of samples for one channel, note that channelSampleNumbers must not smaller than sampleTimeThreshhold.

uint8_t sampleTimeThreshhold

Specify that for one channel, when (sampleTimeThreshhold + 1) sample results are "1",the final result is "1", otherwise the final result is "0", note that the sampleTimeThreshhold must not be larger than channelSampleNumbers.

lpcmp_roundrobin_clock_source_t roundrobinClockSource

Decide which clock source to choose in round robin mode.

lpcmp_roundrobin_trigger_source_t roundrobinTriggerSource

Decide which trigger source to choose in round robin mode.

lpcmp_roundrobin_fixedmuxport_t fixedMuxPort

Decide which mux port to choose as fixed channel in round robin mode.

uint8_t fixedChannel

Indicate which channel of the fixed mux port is used in round robin mode.

uint8_t checkerChannelMask

Indicate which channel of the non-fixed mux port to check its voltage value in round robin mode, for example, if checkerChannelMask set to 0x11U means select channel 0 and channel 4 as checker channel.

2.49 LPI2C: Low Power Inter-Integrated Circuit Driver

void LPI2C_DriverIRQHandler(uint32_t instance)

LPI2C driver IRQ handler common entry.

This function provides the common IRQ request entry for LPI2C.

Parameters

- instance – LPI2C instance.

FSL_LPI2C_DRIVER_VERSION

LPI2C driver version.

LPI2C status return codes.

Values:

enumerator kStatus_LPI2C_Busy

The master is already performing a transfer.

enumerator kStatus_LPI2C_Idle

The slave driver is idle.

enumerator kStatus_LPI2C_Nak

The slave device sent a NAK in response to a byte.

enumerator kStatus_LPI2C_FifoError

FIFO under run or overrun.

enumerator kStatus_LPI2C_BitError

Transferred bit was not seen on the bus.

enumerator kStatus_LPI2C_ArbitrationLost

Arbitration lost error.

enumerator kStatus_LPI2C_PinLowTimeout

SCL or SDA were held low longer than the timeout.

enumerator kStatus_LPI2C_NoTransferInProgress

Attempt to abort a transfer when one is not in progress.

enumerator kStatus_LPI2C_DmaRequestFail

DMA request failed.

enumerator kStatus_LPI2C_Timeout

Timeout polling status flags.

IRQn_Type const kLpi2cMasterIrqs[]

Array to map LPI2C instance number to IRQ number, used internally for LPI2C master interrupt and EDMA transactional APIs.

IRQn_Type const kLpi2cSlaveIrqs[]

lpi2c_master_isr_t s_lpi2cMasterIsr

Pointer to master IRQ handler for each instance, used internally for LPI2C master interrupt and EDMA transactional APIs.

void *s_lpi2cMasterHandle[]

Pointers to master handles for each instance, used internally for LPI2C master interrupt and EDMA transactional APIs.

uint32_t LPI2C_GetInstance(LPI2C_Type *base)

Returns an instance number given a base address.

If an invalid base address is passed, debug builds will assert. Release builds will just return instance number 0.

Parameters

- base – The LPI2C peripheral base address.

Returns

LPI2C instance number starting from 0.

I2C_RETRY_TIMES

Retry times for waiting flag.

2.50 LPI2C Master Driver

void LPI2C_MasterGetDefaultConfig(*lpi2c_master_config_t* *masterConfig)

Provides a default configuration for the LPI2C master peripheral.

This function provides the following default configuration for the LPI2C master peripheral:

```
masterConfig->enableMaster            = true;
masterConfig->debugEnable             = false;
masterConfig->ignoreAck               = false;
masterConfig->pinConfig               = kLPI2C_2PinOpenDrain;
masterConfig->baudRate_Hz             = 100000U;
masterConfig->busIdleTimeout_ns       = 0;
masterConfig->pinLowTimeout_ns        = 0;
masterConfig->sdaGlitchFilterWidth_ns = 0;
masterConfig->sclGlitchFilterWidth_ns = 0;
masterConfig->hostRequest.enable      = false;
masterConfig->hostRequest.source      = kLPI2C_HostRequestExternalPin;
masterConfig->hostRequest.polarity    = kLPI2C_HostRequestPinActiveHigh;
```

After calling this function, you can override any settings in order to customize the configuration, prior to initializing the master driver with *LPI2C_MasterInit()*.

Parameters

- masterConfig – **[out]** User provided configuration structure for default values. Refer to *lpi2c_master_config_t*.

void LPI2C_MasterInit(LPI2C_Type *base, const *lpi2c_master_config_t* *masterConfig, uint32_t sourceClock_Hz)

Initializes the LPI2C master peripheral.

This function enables the peripheral clock and initializes the LPI2C master peripheral as described by the user provided configuration. A software reset is performed prior to configuration.

Parameters

- base – The LPI2C peripheral base address.
- masterConfig – User provided peripheral configuration. Use *LPI2C_MasterGetDefaultConfig()* to get a set of defaults that you can override.
- sourceClock_Hz – Frequency in Hertz of the LPI2C functional clock. Used to calculate the baud rate divisors, filter widths, and timeout periods.

void LPI2C_MasterDeinit(LPI2C_Type *base)

Deinitializes the LPI2C master peripheral.

This function disables the LPI2C master peripheral and gates the clock. It also performs a software reset to restore the peripheral to reset conditions.

Parameters

- base – The LPI2C peripheral base address.

void LPI2C_MasterConfigureDataMatch(LPI2C_Type *base, const *lpi2c_data_match_config_t* *matchConfig)

Configures LPI2C master data match feature.

Parameters

- base – The LPI2C peripheral base address.
- matchConfig – Settings for the data match feature.

status_t LPI2C_MasterCheckAndClearError(LPI2C_Type *base, uint32_t status)

Convert provided flags to status code, and clear any errors if present.

Parameters

- base – The LPI2C peripheral base address.
- status – Current status flags value that will be checked.

Return values

- kStatus_Success –
- kStatus_LPI2C_PinLowTimeout –
- kStatus_LPI2C_ArbitrationLost –
- kStatus_LPI2C_Nak –
- kStatus_LPI2C_FifoError –

status_t LPI2C_CheckForBusyBus(LPI2C_Type *base)

Make sure the bus isn't already busy.

A busy bus is allowed if we are the one driving it.

Parameters

- base – The LPI2C peripheral base address.

Return values

- kStatus_Success –
- kStatus_LPI2C_Busy –

static inline void LPI2C_MasterReset(LPI2C_Type *base)

Performs a software reset.

Restores the LPI2C master peripheral to reset conditions.

Parameters

- base – The LPI2C peripheral base address.

static inline void LPI2C_MasterEnable(LPI2C_Type *base, bool enable)

Enables or disables the LPI2C module as master.

Parameters

- base – The LPI2C peripheral base address.
- enable – Pass true to enable or false to disable the specified LPI2C as master.

static inline uint32_t LPI2C_MasterGetStatusFlags(LPI2C_Type *base)

Gets the LPI2C master status flags.

A bit mask with the state of all LPI2C master status flags is returned. For each flag, the corresponding bit in the return value is set if the flag is asserted.

See also:

_lpi2c_master_flags

Parameters

- base – The LPI2C peripheral base address.

Returns

State of the status flags:

- 1: related status flag is set.
- 0: related status flag is not set.

static inline void LPI2C_MasterClearStatusFlags(LPI2C_Type *base, uint32_t statusMask)

Clears the LPI2C master status flag state.

The following status register flags can be cleared:

- *kLPI2C_MasterEndOfPacketFlag*
- *kLPI2C_MasterStopDetectFlag*
- *kLPI2C_MasterNackDetectFlag*
- *kLPI2C_MasterArbitrationLostFlag*
- *kLPI2C_MasterFifoErrFlag*
- *kLPI2C_MasterPinLowTimeoutFlag*

- *kLPI2C_MasterDataMatchFlag*

Attempts to clear other flags has no effect.

See also:

_lpi2c_master_flags.

Parameters

- base – The LPI2C peripheral base address.
- statusMask – A bitmask of status flags that are to be cleared. The mask is composed of _lpi2c_master_flags enumerators OR'd together. You may pass the result of a previous call to *LPI2C_MasterGetStatusFlags()*.

static inline void LPI2C_MasterEnableInterrupts(LPI2C_Type *base, uint32_t interruptMask)

Enables the LPI2C master interrupt requests.

All flags except *kLPI2C_MasterBusyFlag* and *kLPI2C_MasterBusBusyFlag* can be enabled as interrupts.

Parameters

- base – The LPI2C peripheral base address.
- interruptMask – Bit mask of interrupts to enable. See _lpi2c_master_flags for the set of constants that should be OR'd together to form the bit mask.

static inline void LPI2C_MasterDisableInterrupts(LPI2C_Type *base, uint32_t interruptMask)

Disables the LPI2C master interrupt requests.

All flags except *kLPI2C_MasterBusyFlag* and *kLPI2C_MasterBusBusyFlag* can be enabled as interrupts.

Parameters

- base – The LPI2C peripheral base address.
- interruptMask – Bit mask of interrupts to disable. See _lpi2c_master_flags for the set of constants that should be OR'd together to form the bit mask.

static inline uint32_t LPI2C_MasterGetEnabledInterrupts(LPI2C_Type *base)

Returns the set of currently enabled LPI2C master interrupt requests.

Parameters

- base – The LPI2C peripheral base address.

Returns

A bitmask composed of _lpi2c_master_flags enumerators OR'd together to indicate the set of enabled interrupts.

static inline void LPI2C_MasterEnableDMA(LPI2C_Type *base, bool enableTx, bool enableRx)

Enables or disables LPI2C master DMA requests.

Parameters

- base – The LPI2C peripheral base address.
- enableTx – Enable flag for transmit DMA request. Pass true for enable, false for disable.
- enableRx – Enable flag for receive DMA request. Pass true for enable, false for disable.

static inline uint32_t LPI2C_MasterGetTxFifoAddress(LPI2C_Type *base)

Gets LPI2C master transmit data register address for DMA transfer.

Parameters

- base – The LPI2C peripheral base address.

Returns

The LPI2C Master Transmit Data Register address.

static inline uint32_t LPI2C_MasterGetRxFifoAddress(LPI2C_Type *base)

Gets LPI2C master receive data register address for DMA transfer.

Parameters

- base – The LPI2C peripheral base address.

Returns

The LPI2C Master Receive Data Register address.

static inline void LPI2C_MasterSetWatermarks(LPI2C_Type *base, size_t txWords, size_t rxWords)

Sets the watermarks for LPI2C master FIFOs.

Parameters

- base – The LPI2C peripheral base address.
- txWords – Transmit FIFO watermark value in words. The *kLPI2C_MasterTxReadyFlag* flag is set whenever the number of words in the transmit FIFO is equal or less than *txWords*. Writing a value equal or greater than the FIFO size is truncated.
- rxWords – Receive FIFO watermark value in words. The *kLPI2C_MasterRxReadyFlag* flag is set whenever the number of words in the receive FIFO is greater than *rxWords*. Writing a value equal or greater than the FIFO size is truncated.

static inline void LPI2C_MasterGetFifoCounts(LPI2C_Type *base, size_t *rxCount, size_t *txCount)

Gets the current number of words in the LPI2C master FIFOs.

Parameters

- base – The LPI2C peripheral base address.
- txCount – **[out]** Pointer through which the current number of words in the transmit FIFO is returned. Pass NULL if this value is not required.
- rxCount – **[out]** Pointer through which the current number of words in the receive FIFO is returned. Pass NULL if this value is not required.

void LPI2C_MasterSetBaudRate(LPI2C_Type *base, uint32_t sourceClock_Hz, uint32_t baudRate_Hz)

Sets the I2C bus frequency for master transactions.

The LPI2C master is automatically disabled and re-enabled as necessary to configure the baud rate. Do not call this function during a transfer, or the transfer is aborted.

Note: Please note that the second parameter is the clock frequency of LPI2C module, the third parameter means user configured bus baudrate, this implementation is different from other I2C drivers which use baudrate configuration as second parameter and source clock frequency as third parameter.

Parameters

- base – The LPI2C peripheral base address.
- sourceClock_Hz – LPI2C functional clock frequency in Hertz.
- baudRate_Hz – Requested bus frequency in Hertz.

static inline bool LPI2C_MasterGetBusIdleState(LPI2C_Type *base)

Returns whether the bus is idle.

Requires the master mode to be enabled.

Parameters

- base – The LPI2C peripheral base address.

Return values

- true – Bus is busy.
- false – Bus is idle.

status_t LPI2C_MasterStart(LPI2C_Type *base, uint8_t address, *lpi2c_direction_t* dir)

Sends a START signal and slave address on the I2C bus.

This function is used to initiate a new master mode transfer. First, the bus state is checked to ensure that another master is not occupying the bus. Then a START signal is transmitted, followed by the 7-bit address specified in the *address* parameter. Note that this function does not actually wait until the START and address are successfully sent on the bus before returning.

Parameters

- base – The LPI2C peripheral base address.
- address – 7-bit slave device address, in bits [6:0].
- dir – Master transfer direction, either *kLPI2C_Read* or *kLPI2C_Write*. This parameter is used to set the R/w bit (bit 0) in the transmitted slave address.

Return values

- kStatus_Success – START signal and address were successfully enqueued in the transmit FIFO.
- kStatus_LPI2C_Busy – Another master is currently utilizing the bus.

static inline *status_t* LPI2C_MasterRepeatedStart(LPI2C_Type *base, uint8_t address, *lpi2c_direction_t* dir)

Sends a repeated START signal and slave address on the I2C bus.

This function is used to send a Repeated START signal when a transfer is already in progress. Like *LPI2C_MasterStart()*, it also sends the specified 7-bit address.

Note: This function exists primarily to maintain compatible APIs between LPI2C and I2C drivers, as well as to better document the intent of code that uses these APIs.

Parameters

- base – The LPI2C peripheral base address.
- address – 7-bit slave device address, in bits [6:0].
- dir – Master transfer direction, either *kLPI2C_Read* or *kLPI2C_Write*. This parameter is used to set the R/w bit (bit 0) in the transmitted slave address.

Return values

- kStatus_Success – Repeated START signal and address were successfully enqueued in the transmit FIFO.
- kStatus_LPI2C_Busy – Another master is currently utilizing the bus.

status_t LPI2C_MasterSend(LPI2C_Type *base, void *txBuff, size_t txSize)

Performs a polling send transfer on the I2C bus.

Sends up to *txSize* number of bytes to the previously addressed slave device. The slave may reply with a NAK to any byte in order to terminate the transfer early. If this happens, this function returns *kStatus_LPI2C_Nak*.

Parameters

- base – The LPI2C peripheral base address.
- txBuff – The pointer to the data to be transferred.
- txSize – The length in bytes of the data to be transferred.

Return values

- kStatus_Success – Data was sent successfully.
- kStatus_LPI2C_Busy – Another master is currently utilizing the bus.
- kStatus_LPI2C_Nak – The slave device sent a NAK in response to a byte.
- kStatus_LPI2C_FifoError – FIFO under run or over run.
- kStatus_LPI2C_ArbitrationLost – Arbitration lost error.
- kStatus_LPI2C_PinLowTimeout – SCL or SDA were held low longer than the timeout.

status_t LPI2C_MasterReceive(LPI2C_Type *base, void *rxBuff, size_t rxSize)

Performs a polling receive transfer on the I2C bus.

Parameters

- base – The LPI2C peripheral base address.
- rxBuff – The pointer to the data to be transferred.
- rxSize – The length in bytes of the data to be transferred.

Return values

- kStatus_Success – Data was received successfully.
- kStatus_LPI2C_Busy – Another master is currently utilizing the bus.
- kStatus_LPI2C_Nak – The slave device sent a NAK in response to a byte.
- kStatus_LPI2C_FifoError – FIFO under run or overrun.
- kStatus_LPI2C_ArbitrationLost – Arbitration lost error.
- kStatus_LPI2C_PinLowTimeout – SCL or SDA were held low longer than the timeout.

status_t LPI2C_MasterStop(LPI2C_Type *base)

Sends a STOP signal on the I2C bus.

This function does not return until the STOP signal is seen on the bus, or an error occurs.

Parameters

- base – The LPI2C peripheral base address.

Return values

- kStatus_Success – The STOP signal was successfully sent on the bus and the transaction terminated.
- kStatus_LPI2C_Busy – Another master is currently utilizing the bus.
- kStatus_LPI2C_Nak – The slave device sent a NAK in response to a byte.
- kStatus_LPI2C_FifoError – FIFO under run or overrun.
- kStatus_LPI2C_ArbitrationLost – Arbitration lost error.
- kStatus_LPI2C_PinLowTimeout – SCL or SDA were held low longer than the timeout.

status_t LPI2C_MasterTransferBlocking(LPI2C_Type *base, *lpi2c_master_transfer_t* *transfer)

Performs a master polling transfer on the I2C bus.

Note: The API does not return until the transfer succeeds or fails due to error happens during transfer.

Parameters

- base – The LPI2C peripheral base address.
- transfer – Pointer to the transfer structure.

Return values

- kStatus_Success – Data was received successfully.
- kStatus_LPI2C_Busy – Another master is currently utilizing the bus.
- kStatus_LPI2C_Nak – The slave device sent a NAK in response to a byte.
- kStatus_LPI2C_FifoError – FIFO under run or overrun.
- kStatus_LPI2C_ArbitrationLost – Arbitration lost error.
- kStatus_LPI2C_PinLowTimeout – SCL or SDA were held low longer than the timeout.

void LPI2C_MasterTransferCreateHandle(LPI2C_Type *base, *lpi2c_master_handle_t* *handle, *lpi2c_master_transfer_callback_t* callback, void *userData)

Creates a new handle for the LPI2C master non-blocking APIs.

The creation of a handle is for use with the non-blocking APIs. Once a handle is created, there is not a corresponding destroy handle. If the user wants to terminate a transfer, the *LPI2C_MasterTransferAbort()* API shall be called.

Note: The function also enables the NVIC IRQ for the input LPI2C. Need to notice that on some SoCs the LPI2C IRQ is connected to INTMUX, in this case user needs to enable the associated INTMUX IRQ in application.

Parameters

- base – The LPI2C peripheral base address.
- handle – **[out]** Pointer to the LPI2C master driver handle.
- callback – User provided pointer to the asynchronous callback function.
- userData – User provided pointer to the application callback data.

status_t LPI2C_MasterTransferNonBlocking(LPI2C_Type *base, *lpi2c_master_handle_t* *handle, *lpi2c_master_transfer_t* *transfer)

Performs a non-blocking transaction on the I2C bus.

Parameters

- base – The LPI2C peripheral base address.
- handle – Pointer to the LPI2C master driver handle.
- transfer – The pointer to the transfer descriptor.

Return values

- kStatus_Success – The transaction was started successfully.
- kStatus_LPI2C_Busy – Either another master is currently utilizing the bus, or a non-blocking transaction is already in progress.

status_t LPI2C_MasterTransferGetCount(LPI2C_Type *base, *lpi2c_master_handle_t* *handle, size_t *count)

Returns number of bytes transferred so far.

Parameters

- base – The LPI2C peripheral base address.
- handle – Pointer to the LPI2C master driver handle.
- count – **[out]** Number of bytes transferred so far by the non-blocking transaction.

Return values

- kStatus_Success –
- kStatus_NoTransferInProgress – There is not a non-blocking transaction currently in progress.

void LPI2C_MasterTransferAbort(LPI2C_Type *base, *lpi2c_master_handle_t* *handle)

Terminates a non-blocking LPI2C master transmission early.

Note: It is not safe to call this function from an IRQ handler that has a higher priority than the LPI2C peripheral's IRQ priority.

Parameters

- base – The LPI2C peripheral base address.
- handle – Pointer to the LPI2C master driver handle.

void LPI2C_MasterTransferHandleIRQ(LPI2C_Type *base, void *lpi2cMasterHandle)

Reusable routine to handle master interrupts.

Note: This function does not need to be called unless you are reimplementing the non-blocking API's interrupt handler routines to add special functionality.

Parameters

- base – The LPI2C peripheral base address.
- lpi2cMasterHandle – Pointer to the LPI2C master driver handle.

enum _lpi2c_master_flags

LPI2C master peripheral flags.

The following status register flags can be cleared:

- *kLPI2C_MasterEndOfPacketFlag*
- *kLPI2C_MasterStopDetectFlag*
- *kLPI2C_MasterNackDetectFlag*
- *kLPI2C_MasterArbitrationLostFlag*
- *kLPI2C_MasterFifoErrFlag*
- *kLPI2C_MasterPinLowTimeoutFlag*
- *kLPI2C_MasterDataMatchFlag*

All flags except *kLPI2C_MasterBusyFlag* and *kLPI2C_MasterBusBusyFlag* can be enabled as interrupts.

Note: These enums are meant to be OR'd together to form a bit mask.

Values:

enumerator kLPI2C_MasterTxReadyFlag

Transmit data flag

enumerator kLPI2C_MasterRxReadyFlag

Receive data flag

enumerator kLPI2C_MasterEndOfPacketFlag

End Packet flag

enumerator kLPI2C_MasterStopDetectFlag

Stop detect flag

enumerator kLPI2C_MasterNackDetectFlag

NACK detect flag

enumerator kLPI2C_MasterArbitrationLostFlag

Arbitration lost flag

enumerator kLPI2C_MasterFifoErrFlag

FIFO error flag

enumerator kLPI2C_MasterPinLowTimeoutFlag

Pin low timeout flag

enumerator kLPI2C_MasterDataMatchFlag

Data match flag

enumerator kLPI2C_MasterBusyFlag

Master busy flag

enumerator kLPI2C_MasterBusBusyFlag
Bus busy flag

enumerator kLPI2C_MasterClearFlags
All flags which are cleared by the driver upon starting a transfer.

enumerator kLPI2C_MasterIrqFlags
IRQ sources enabled by the non-blocking transactional API.

enumerator kLPI2C_MasterErrorFlags
Errors to check for.

enum _lpi2c_direction
Direction of master and slave transfers.
Values:

enumerator kLPI2C_Write
Master transmit.

enumerator kLPI2C_Read
Master receive.

enum _lpi2c_master_pin_config
LPI2C pin configuration.
Values:

enumerator kLPI2C_2PinOpenDrain
LPI2C Configured for 2-pin open drain mode

enumerator kLPI2C_2PinOutputOnly
LPI2C Configured for 2-pin output only mode (ultra-fast mode)

enumerator kLPI2C_2PinPushPull
LPI2C Configured for 2-pin push-pull mode

enumerator kLPI2C_4PinPushPull
LPI2C Configured for 4-pin push-pull mode

enumerator kLPI2C_2PinOpenDrainWithSeparateSlave
LPI2C Configured for 2-pin open drain mode with separate LPI2C slave

enumerator kLPI2C_2PinOutputOnlyWithSeparateSlave
LPI2C Configured for 2-pin output only mode(ultra-fast mode) with separate LPI2C slave

enumerator kLPI2C_2PinPushPullWithSeparateSlave
LPI2C Configured for 2-pin push-pull mode with separate LPI2C slave

enumerator kLPI2C_4PinPushPullWithInvertedOutput
LPI2C Configured for 4-pin push-pull mode(inverted outputs)

enum _lpi2c_host_request_source
LPI2C master host request selection.
Values:

enumerator kLPI2C_HostRequestExternalPin
Select the LPI2C_HREQ pin as the host request input

enumerator kLPI2C_HostRequestInputTrigger
Select the input trigger as the host request input

enum _lpi2c_host_request_polarity
LPI2C master host request pin polarity configuration.
Values:

enumerator kLPI2C_HostRequestPinActiveLow
Configure the LPI2C_HREQ pin active low

enumerator kLPI2C_HostRequestPinActiveHigh
Configure the LPI2C_HREQ pin active high

enum _lpi2c_data_match_config_mode
LPI2C master data match configuration modes.
Values:

enumerator kLPI2C_MatchDisabled
LPI2C Match Disabled

enumerator kLPI2C_1stWordEqualsM0OrM1
LPI2C Match Enabled and 1st data word equals MATCH0 OR MATCH1

enumerator kLPI2C_AnyWordEqualsM0OrM1
LPI2C Match Enabled and any data word equals MATCH0 OR MATCH1

enumerator kLPI2C_1stWordEqualsM0And2ndWordEqualsM1
LPI2C Match Enabled and 1st data word equals MATCH0, 2nd data equals MATCH1

enumerator kLPI2C_AnyWordEqualsM0AndNextWordEqualsM1
LPI2C Match Enabled and any data word equals MATCH0, next data equals MATCH1

enumerator kLPI2C_1stWordAndM1EqualsM0AndM1
LPI2C Match Enabled and 1st data word and MATCH0 equals MATCH0 and MATCH1

enumerator kLPI2C_AnyWordAndM1EqualsM0AndM1
LPI2C Match Enabled and any data word and MATCH0 equals MATCH0 and MATCH1

enum _lpi2c_master_transfer_flags

Transfer option flags.

Note: These enumerations are intended to be OR'd together to form a bit mask of options for the *_lpi2c_master_transfer::flags* field.

Values:

enumerator kLPI2C_TransferDefaultFlag

Transfer starts with a start signal, stops with a stop signal.

enumerator kLPI2C_TransferNoStartFlag

Don't send a start condition, address, and sub address

enumerator kLPI2C_TransferNoStopFlag

Don't send a stop condition.

typedef enum *_lpi2c_direction* lpi2c_direction_t

Direction of master and slave transfers.

typedef enum *_lpi2c_master_pin_config* lpi2c_master_pin_config_t

LPI2C pin configuration.

typedef enum *_lpi2c_host_request_source* lpi2c_host_request_source_t

LPI2C master host request selection.

typedef enum *_lpi2c_host_request_polarity* lpi2c_host_request_polarity_t

LPI2C master host request pin polarity configuration.

typedef struct *_lpi2c_master_config* lpi2c_master_config_t

Structure with settings to initialize the LPI2C master module.

This structure holds configuration settings for the LPI2C peripheral. To initialize this structure to reasonable defaults, call the *LPI2C_MasterGetDefaultConfig()* function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

typedef enum *_lpi2c_data_match_config_mode* lpi2c_data_match_config_mode_t

LPI2C master data match configuration modes.

typedef struct *_lpi2c_match_config* lpi2c_data_match_config_t

LPI2C master data match configuration structure.

typedef struct *_lpi2c_master_transfer* lpi2c_master_transfer_t

LPI2C master descriptor of the transfer.

typedef struct *_lpi2c_master_handle* lpi2c_master_handle_t

LPI2C master handle of the transfer.

typedef void (*lpi2c_master_transfer_callback_t)(LPI2C_Type *base, *lpi2c_master_handle_t* *handle, *status_t* completionStatus, void *userData)

Master completion callback function pointer type.

This callback is used only for the non-blocking master transfer API. Specify the callback you wish to use in the call to *LPI2C_MasterTransferCreateHandle()*.

Param base
The LPI2C peripheral base address.

Param handle
Pointer to the LPI2C master driver handle.

Param completionStatus
Either kStatus_Success or an error code describing how the transfer completed.

Param userData
Arbitrary pointer-sized value passed from the application.

typedef void (*lpi2c_master_isr_t)(LPI2C_Type *base, void *handle)

Typedef for master interrupt handler, used internally for LPI2C master interrupt and EDMA transactional APIs.

struct _lpi2c_master_config

#include <fsl_lpi2c.h> Structure with settings to initialize the LPI2C master module.

This structure holds configuration settings for the LPI2C peripheral. To initialize this structure to reasonable defaults, call the *LPI2C_MasterGetDefaultConfig()* function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

Public Members

bool enableMaster

Whether to enable master mode.

bool enableDoze

Whether master is enabled in doze mode.

bool debugEnable

Enable transfers to continue when halted in debug mode.

bool ignoreAck

Whether to ignore ACK/NACK.

lpi2c_master_pin_config_t pinConfig

The pin configuration option.

uint32_t baudRate_Hz

Desired baud rate in Hertz.

uint32_t busIdleTimeout_ns
: Bus idle timeout in nanoseconds. Set to 0 to disable.

uint32_t pinLowTimeout_ns
: Pin low timeout in nanoseconds. Set to 0 to disable.

uint8_t sdaGlitchFilterWidth_ns
: Width in nanoseconds of glitch filter on SDA pin. Set to 0 to disable.

uint8_t sclGlitchFilterWidth_ns
: Width in nanoseconds of glitch filter on SCL pin. Set to 0 to disable.

struct *_lpi2c_master_config* hostRequest
: Host request options.

struct __lpi2c_match_config
: *#include <fsl_lpi2c.h>* LPI2C master data match configuration structure.

Public Members

lpi2c_data_match_config_mode_t matchMode
: Data match configuration setting.

bool rxDataMatchOnly
: When set to true, received data is ignored until a successful match.

uint32_t match0
: Match value 0.

uint32_t match1
: Match value 1.

struct __lpi2c_master_transfer
: *#include <fsl_lpi2c.h>* Non-blocking transfer descriptor structure.

  This structure is used to pass transaction parameters to the *LPI2C_MasterTransferNonBlocking()* API.

Public Members

uint32_t flags
: Bit mask of options for the transfer. See enumeration *_lpi2c_master_transfer_flags* for available options. Set to 0 or *kLPI2C_TransferDefaultFlag* for normal transfers.

uint16_t slaveAddress
: The 7-bit slave address.

lpi2c_direction_t direction
Either *kLPI2C_Read* or *kLPI2C_Write*.

uint32_t subaddress
Sub address. Transferred MSB first.

size_t subaddressSize
Length of sub address to send in bytes. Maximum size is 4 bytes.

void *data
Pointer to data to transfer.

size_t dataSize
Number of bytes to transfer.

struct __lpi2c_master_handle
#include <fsl_lpi2c.h> Driver handle for master non-blocking APIs.

Note: The contents of this structure are private and subject to change.

Public Members

uint8_t state
Transfer state machine current state.

uint16_t remainingBytes
Remaining byte count in current state.

uint8_t *buf
Buffer pointer for current state.

uint16_t commandBuffer[6]
LPI2C command sequence. When all 6 command words are used: Start&addr&write[1 word] + subaddr[4 words] + restart&addr&read[1 word]

lpi2c_master_transfer_t transfer
Copy of the current transfer info.

lpi2c_master_transfer_callback_t completionCallback
Callback function pointer.

void *userData
Application data passed to callback.

uint16_t chunkSize
Remaining byte count in current chunk.

struct hostRequest

Public Members

bool enable

Enable host request.

lpi2c_host_request_source_t source

Host request source.

lpi2c_host_request_polarity_t polarity

Host request pin polarity.

2.51 LPI2C Master DMA Driver

void LPI2C_MasterCreateEDMAHandle(LPI2C_Type *base, *lpi2c_master_edma_handle_t* *handle, *edma_handle_t* *rxDmaHandle, *edma_handle_t* *txDmaHandle, *lpi2c_master_edma_transfer_callback_t* callback, void *userData)

Create a new handle for the LPI2C master DMA APIs.

The creation of a handle is for use with the DMA APIs. Once a handle is created, there is not a corresponding destroy handle. If the user wants to terminate a transfer, the *LPI2C_MasterTransferAbortEDMA()* API shall be called.

For devices where the LPI2C send and receive DMA requests are OR'd together, the *txDmaHandle* parameter is ignored and may be set to NULL.

Parameters

- base – The LPI2C peripheral base address.
- handle – **[out]** Pointer to the LPI2C master driver handle.
- rxDmaHandle – Handle for the eDMA receive channel. Created by the user prior to calling this function.
- txDmaHandle – Handle for the eDMA transmit channel. Created by the user prior to calling this function.
- callback – User provided pointer to the asynchronous callback function.
- userData – User provided pointer to the application callback data.

status_t LPI2C_MasterTransferEDMA(LPI2C_Type *base, *lpi2c_master_edma_handle_t* *handle, *lpi2c_master_transfer_t* *transfer)

Performs a non-blocking DMA-based transaction on the I2C bus.

The callback specified when the *handle* was created is invoked when the transaction has completed.

Parameters

- base – The LPI2C peripheral base address.
- handle – Pointer to the LPI2C master driver handle.
- transfer – The pointer to the transfer descriptor.

Return values

- kStatus_Success – The transaction was started successfully.

- kStatus_LPI2C_Busy – Either another master is currently utilizing the bus, or another DMA transaction is already in progress.

status_t LPI2C_MasterTransferGetCountEDMA(LPI2C_Type *base, *lpi2c_master_edma_handle_t* *handle, size_t *count)

Returns number of bytes transferred so far.

Parameters

- base – The LPI2C peripheral base address.
- handle – Pointer to the LPI2C master driver handle.
- count – **[out]** Number of bytes transferred so far by the non-blocking transaction.

Return values

- kStatus_Success –
- kStatus_NoTransferInProgress – There is not a DMA transaction currently in progress.

status_t LPI2C_MasterTransferAbortEDMA(LPI2C_Type *base, *lpi2c_master_edma_handle_t* *handle)

Terminates a non-blocking LPI2C master transmission early.

Note: It is not safe to call this function from an IRQ handler that has a higher priority than the eDMA peripheral's IRQ priority.

Parameters

- base – The LPI2C peripheral base address.
- handle – Pointer to the LPI2C master driver handle.

Return values

- kStatus_Success – A transaction was successfully aborted.
- kStatus_LPI2C_Idle – There is not a DMA transaction currently in progress.

typedef struct *_lpi2c_master_edma_handle* lpi2c_master_edma_handle_t

LPI2C master EDMA handle of the transfer.

typedef void (*lpi2c_master_edma_transfer_callback_t)(LPI2C_Type *base, *lpi2c_master_edma_handle_t* *handle, *status_t* completionStatus, void *userData)

Master DMA completion callback function pointer type.

This callback is used only for the non-blocking master transfer API. Specify the callback you wish to use in the call to *LPI2C_MasterCreateEDMAHandle()*.

Param base
The LPI2C peripheral base address.

Param handle
Handle associated with the completed transfer.

Param completionStatus
Either kStatus_Success or an error code describing how the transfer completed.

Param userData
Arbitrary pointer-sized value passed from the application.

struct _lpi2c_master_edma_handle

#include <fsl_lpi2c_edma.h> Driver handle for master DMA APIs.

Note: The contents of this structure are private and subject to change.

Public Members

LPI2C_Type *base

LPI2C base pointer.

bool isBusy

Transfer state machine current state.

uint8_t nbytes

eDMA minor byte transfer count initially configured.

uint16_t commandBuffer[20U]

LPI2C command sequence. When all 10 command words are used: Start&addr&write[1 word] + subaddr[4 words] + restart&addr&read[1 word] + receive&Size[4 words]

lpi2c_master_transfer_t transfer

Copy of the current transfer info.

lpi2c_master_edma_transfer_callback_t completionCallback

Callback function pointer.

void *userData

Application data passed to callback.

edma_handle_t *rx

Handle for receive DMA channel.

edma_handle_t *tx

Handle for transmit DMA channel.

edma_tcd_t tcds[3]

Software TCD. Three are allocated to provide enough room to align to 32-bytes.

2.52 LPI2C Slave Driver

void LPI2C_SlaveGetDefaultConfig(*lpi2c_slave_config_t* *slaveConfig)

Provides a default configuration for the LPI2C slave peripheral.

This function provides the following default configuration for the LPI2C slave peripheral:

```
slaveConfig->enableSlave              = true;
slaveConfig->address0                 = 0U;
slaveConfig->address1                 = 0U;
slaveConfig->addressMatchMode         = kLPI2C_MatchAddress0;
slaveConfig->filterDozeEnable         = true;
slaveConfig->filterEnable             = true;
slaveConfig->enableGeneralCall        = false;
slaveConfig->sclStall.enableAck       = false;
slaveConfig->sclStall.enableTx        = true;
slaveConfig->sclStall.enableRx        = true;
slaveConfig->sclStall.enableAddress   = true;
slaveConfig->ignoreAck                = false;
slaveConfig->enableReceivedAddressRead = false;
slaveConfig->sdaGlitchFilterWidth_ns  = 0;
slaveConfig->sclGlitchFilterWidth_ns  = 0;
slaveConfig->dataValidDelay_ns        = 0;
slaveConfig->clockHoldTime_ns         = 0;
```

After calling this function, override any settings to customize the configuration, prior to initializing the master driver with *LPI2C_SlaveInit()*. Be sure to override at least the *address0* member of the configuration structure with the desired slave address.

Parameters

- slaveConfig – **[out]** User provided configuration structure that is set to default values. Refer to *lpi2c_slave_config_t*.

void LPI2C_SlaveInit(LPI2C_Type *base, const *lpi2c_slave_config_t* *slaveConfig, uint32_t sourceClock_Hz)

Initializes the LPI2C slave peripheral.

This function enables the peripheral clock and initializes the LPI2C slave peripheral as described by the user provided configuration.

Parameters

- base – The LPI2C peripheral base address.
- slaveConfig – User provided peripheral configuration. Use *LPI2C_SlaveGetDefaultConfig()* to get a set of defaults that you can override.
- sourceClock_Hz – Frequency in Hertz of the LPI2C functional clock. Used to calculate the filter widths, data valid delay, and clock hold time.

void LPI2C_SlaveDeinit(LPI2C_Type *base)

Deinitializes the LPI2C slave peripheral.

This function disables the LPI2C slave peripheral and gates the clock. It also performs a software reset to restore the peripheral to reset conditions.

Parameters

- base – The LPI2C peripheral base address.

static inline void LPI2C_SlaveReset(LPI2C_Type *base)

Performs a software reset of the LPI2C slave peripheral.

Parameters

- base – The LPI2C peripheral base address.

static inline void LPI2C_SlaveEnable(LPI2C_Type *base, bool enable)

Enables or disables the LPI2C module as slave.

Parameters

- base – The LPI2C peripheral base address.
- enable – Pass true to enable or false to disable the specified LPI2C as slave.

static inline uint32_t LPI2C_SlaveGetStatusFlags(LPI2C_Type *base)

Gets the LPI2C slave status flags.

A bit mask with the state of all LPI2C slave status flags is returned. For each flag, the corresponding bit in the return value is set if the flag is asserted.

See also:

_lpi2c_slave_flags

Parameters

- base – The LPI2C peripheral base address.

Returns

State of the status flags:

- 1: related status flag is set.
- 0: related status flag is not set.

static inline void LPI2C_SlaveClearStatusFlags(LPI2C_Type *base, uint32_t statusMask)

Clears the LPI2C status flag state.

The following status register flags can be cleared:

- *kLPI2C_SlaveRepeatedStartDetectFlag*
- *kLPI2C_SlaveStopDetectFlag*
- *kLPI2C_SlaveBitErrFlag*
- *kLPI2C_SlaveFifoErrFlag*

Attempts to clear other flags has no effect.

See also:

_lpi2c_slave_flags.

Parameters

- base – The LPI2C peripheral base address.
- statusMask – A bitmask of status flags that are to be cleared. The mask is composed of *_lpi2c_slave_flags* enumerators OR'd together. You may pass the result of a previous call to *LPI2C_SlaveGetStatusFlags()*.

static inline void LPI2C_SlaveEnableInterrupts(LPI2C_Type *base, uint32_t interruptMask)

Enables the LPI2C slave interrupt requests.

All flags except *kLPI2C_SlaveBusyFlag* and *kLPI2C_SlaveBusBusyFlag* can be enabled as interrupts.

Parameters

- base – The LPI2C peripheral base address.

- interruptMask – Bit mask of interrupts to enable. See *_lpi2c_slave_flags* for the set of constants that should be OR'd together to form the bit mask.

static inline void LPI2C_SlaveDisableInterrupts(LPI2C_Type *base, uint32_t interruptMask)

Disables the LPI2C slave interrupt requests.

All flags except *kLPI2C_SlaveBusyFlag* and *kLPI2C_SlaveBusBusyFlag* can be enabled as interrupts.

Parameters

- base – The LPI2C peripheral base address.
- interruptMask – Bit mask of interrupts to disable. See *_lpi2c_slave_flags* for the set of constants that should be OR'd together to form the bit mask.

static inline uint32_t LPI2C_SlaveGetEnabledInterrupts(LPI2C_Type *base)

Returns the set of currently enabled LPI2C slave interrupt requests.

Parameters

- base – The LPI2C peripheral base address.

Returns

A bitmask composed of *_lpi2c_slave_flags* enumerators OR'd together to indicate the set of enabled interrupts.

static inline void LPI2C_SlaveEnableDMA(LPI2C_Type *base, bool enableAddressValid, bool enableRx, bool enableTx)

Enables or disables the LPI2C slave peripheral DMA requests.

Parameters

- base – The LPI2C peripheral base address.
- enableAddressValid – Enable flag for the address valid DMA request. Pass true for enable, false for disable. The address valid DMA request is shared with the receive data DMA request.
- enableRx – Enable flag for the receive data DMA request. Pass true for enable, false for disable.
- enableTx – Enable flag for the transmit data DMA request. Pass true for enable, false for disable.

static inline bool LPI2C_SlaveGetBusIdleState(LPI2C_Type *base)

Returns whether the bus is idle.

Requires the slave mode to be enabled.

Parameters

- base – The LPI2C peripheral base address.

Return values

- true – Bus is busy.
- false – Bus is idle.

static inline void LPI2C_SlaveTransmitAck(LPI2C_Type *base, bool ackOrNack)

Transmits either an ACK or NAK on the I2C bus in response to a byte from the master.

Use this function to send an ACK or NAK when the *kLPI2C_SlaveTransmitAckFlag* is asserted. This only happens if you enable the sclStall.enableAck field of the *lpi2c_slave_config_t* configuration structure used to initialize the slave peripheral.

Parameters

- base – The LPI2C peripheral base address.

- ackOrNack – Pass true for an ACK or false for a NAK.

static inline void LPI2C_SlaveEnableAckStall(LPI2C_Type *base, bool enable)

Enables or disables ACKSTALL.

When enables ACKSTALL, software can transmit either an ACK or NAK on the I2C bus in response to a byte from the master.

Parameters

- base – The LPI2C peripheral base address.
- enable – True will enable ACKSTALL,false will disable ACKSTALL.

static inline uint32_t LPI2C_SlaveGetReceivedAddress(LPI2C_Type *base)

Returns the slave address sent by the I2C master.

This function should only be called if the *kLPI2C_SlaveAddressValidFlag* is asserted.

Parameters

- base – The LPI2C peripheral base address.

Returns

The 8-bit address matched by the LPI2C slave. Bit 0 contains the R/w direction bit, and the 7-bit slave address is in the upper 7 bits.

status_t LPI2C_SlaveSend(LPI2C_Type *base, void *txBuff, size_t txSize, size_t *actualTxSize)

Performs a polling send transfer on the I2C bus.

Parameters

- base – The LPI2C peripheral base address.
- txBuff – The pointer to the data to be transferred.
- txSize – The length in bytes of the data to be transferred.
- actualTxSize – **[out]**

Returns

Error or success status returned by API.

status_t LPI2C_SlaveReceive(LPI2C_Type *base, void *rxBuff, size_t rxSize, size_t *actualRxSize)

Performs a polling receive transfer on the I2C bus.

Parameters

- base – The LPI2C peripheral base address.
- rxBuff – The pointer to the data to be transferred.
- rxSize – The length in bytes of the data to be transferred.
- actualRxSize – **[out]**

Returns

Error or success status returned by API.

void LPI2C_SlaveTransferCreateHandle(LPI2C_Type *base, *lpi2c_slave_handle_t* *handle, *lpi2c_slave_transfer_callback_t* callback, void *userData)

Creates a new handle for the LPI2C slave non-blocking APIs.

The creation of a handle is for use with the non-blocking APIs. Once a handle is created, there is not a corresponding destroy handle. If the user wants to terminate a transfer, the *LPI2C_SlaveTransferAbort()* API shall be called.

Note: The function also enables the NVIC IRQ for the input LPI2C. Need to notice that on some SoCs the LPI2C IRQ is connected to INTMUX, in this case user needs to enable the associated INTMUX IRQ in application.

Parameters

- base – The LPI2C peripheral base address.
- handle – **[out]** Pointer to the LPI2C slave driver handle.
- callback – User provided pointer to the asynchronous callback function.
- userData – User provided pointer to the application callback data.

status_t LPI2C_SlaveTransferNonBlocking(LPI2C_Type *base, *lpi2c_slave_handle_t* *handle, uint32_t eventMask)

Starts accepting slave transfers.

Call this API after calling I2C_SlaveInit() and *LPI2C_SlaveTransferCreateHandle()* to start processing transactions driven by an I2C master. The slave monitors the I2C bus and pass events to the callback that was passed into the call to *LPI2C_SlaveTransferCreateHandle()*. The callback is always invoked from the interrupt context.

The set of events received by the callback is customizable. To do so, set the *eventMask* parameter to the OR'd combination of *lpi2c_slave_transfer_event_t* enumerators for the events you wish to receive. The *kLPI2C_SlaveTransmitEvent* and *kLPI2C_SlaveReceiveEvent* events are always enabled and do not need to be included in the mask. Alternatively, you can pass 0 to get a default set of only the transmit and receive events that are always enabled. In addition, the *kLPI2C_SlaveAllEvents* constant is provided as a convenient way to enable all events.

Parameters

- base – The LPI2C peripheral base address.
- handle – Pointer to lpi2c_slave_handle_t structure which stores the transfer state.
- eventMask – Bit mask formed by OR'ing together *lpi2c_slave_transfer_event_t* enumerators to specify which events to send to the callback. Other accepted values are 0 to get a default set of only the transmit and receive events, and *kLPI2C_SlaveAllEvents* to enable all events.

Return values

- kStatus_Success – Slave transfers were successfully started.
- kStatus_LPI2C_Busy – Slave transfers have already been started on this handle.

status_t LPI2C_SlaveTransferGetCount(LPI2C_Type *base, *lpi2c_slave_handle_t* *handle, size_t *count)

Gets the slave transfer status during a non-blocking transfer.

Parameters

- base – The LPI2C peripheral base address.
- handle – Pointer to i2c_slave_handle_t structure.
- count – **[out]** Pointer to a value to hold the number of bytes transferred. May be NULL if the count is not required.

Return values

- kStatus_Success –
- kStatus_NoTransferInProgress –

void LPI2C_SlaveTransferAbort(LPI2C_Type *base, *lpi2c_slave_handle_t* *handle)

Aborts the slave non-blocking transfers.

Note: This API could be called at any time to stop slave for handling the bus events.

Parameters

- base – The LPI2C peripheral base address.
- handle – Pointer to lpi2c_slave_handle_t structure which stores the transfer state.

void LPI2C_SlaveTransferHandleIRQ(LPI2C_Type *base, *lpi2c_slave_handle_t* *handle)

Reusable routine to handle slave interrupts.

Note: This function does not need to be called unless you are reimplementing the non blocking API's interrupt handler routines to add special functionality.

Parameters

- base – The LPI2C peripheral base address.
- handle – Pointer to lpi2c_slave_handle_t structure which stores the transfer state.

enum _lpi2c_slave_flags

LPI2C slave peripheral flags.

The following status register flags can be cleared:

- *kLPI2C_SlaveRepeatedStartDetectFlag*
- *kLPI2C_SlaveStopDetectFlag*
- *kLPI2C_SlaveBitErrFlag*
- *kLPI2C_SlaveFifoErrFlag*

All flags except *kLPI2C_SlaveBusyFlag* and *kLPI2C_SlaveBusBusyFlag* can be enabled as interrupts.

Note: These enumerations are meant to be OR'd together to form a bit mask.

Values:

enumerator kLPI2C_SlaveTxReadyFlag

Transmit data flag

enumerator kLPI2C_SlaveRxReadyFlag

Receive data flag

enumerator kLPI2C_SlaveAddressValidFlag

Address valid flag

enumerator kLPI2C_SlaveTransmitAckFlag
Transmit ACK flag

enumerator kLPI2C_SlaveRepeatedStartDetectFlag
Repeated start detect flag

enumerator kLPI2C_SlaveStopDetectFlag
Stop detect flag

enumerator kLPI2C_SlaveBitErrFlag
Bit error flag

enumerator kLPI2C_SlaveFifoErrFlag
FIFO error flag

enumerator kLPI2C_SlaveAddressMatch0Flag
Address match 0 flag

enumerator kLPI2C_SlaveAddressMatch1Flag
Address match 1 flag

enumerator kLPI2C_SlaveGeneralCallFlag
General call flag

enumerator kLPI2C_SlaveBusyFlag
Master busy flag

enumerator kLPI2C_SlaveBusBusyFlag
Bus busy flag

enumerator kLPI2C_SlaveClearFlags
All flags which are cleared by the driver upon starting a transfer.

enumerator kLPI2C_SlaveIrqFlags
IRQ sources enabled by the non-blocking transactional API.

enumerator kLPI2C_SlaveErrorFlags
Errors to check for.

enum _lpi2c_slave_address_match
LPI2C slave address match options.
Values:

enumerator kLPI2C_MatchAddress0
Match only address 0.

enumerator kLPI2C_MatchAddress0OrAddress1
Match either address 0 or address 1.

enumerator kLPI2C_MatchAddress0ThroughAddress1

Match a range of slave addresses from address 0 through address 1.

enum _lpi2c_slave_transfer_event

Set of events sent to the callback for non blocking slave transfers.

These event enumerations are used for two related purposes. First, a bit mask created by OR'ing together events is passed to *LPI2C_SlaveTransferNonBlocking()* in order to specify which events to enable. Then, when the slave callback is invoked, it is passed the current event through its *transfer* parameter.

Note: These enumerations are meant to be OR'd together to form a bit mask of events.

Values:

enumerator kLPI2C_SlaveAddressMatchEvent

Received the slave address after a start or repeated start.

enumerator kLPI2C_SlaveTransmitEvent

Callback is requested to provide data to transmit (slave-transmitter role).

enumerator kLPI2C_SlaveReceiveEvent

Callback is requested to provide a buffer in which to place received data (slave-receiver role).

enumerator kLPI2C_SlaveTransmitAckEvent

Callback needs to either transmit an ACK or NACK.

enumerator kLPI2C_SlaveRepeatedStartEvent

A repeated start was detected.

enumerator kLPI2C_SlaveCompletionEvent

A stop was detected, completing the transfer.

enumerator kLPI2C_SlaveAllEvents

Bit mask of all available events.

typedef enum *_lpi2c_slave_address_match* lpi2c_slave_address_match_t

LPI2C slave address match options.

typedef struct *_lpi2c_slave_config* lpi2c_slave_config_t

Structure with settings to initialize the LPI2C slave module.

This structure holds configuration settings for the LPI2C slave peripheral. To initialize this structure to reasonable defaults, call the *LPI2C_SlaveGetDefaultConfig()* function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

typedef enum *_lpi2c_slave_transfer_event* lpi2c_slave_transfer_event_t

Set of events sent to the callback for non blocking slave transfers.

These event enumerations are used for two related purposes. First, a bit mask created by OR'ing together events is passed to *LPI2C_SlaveTransferNonBlocking()* in order to specify which events to enable. Then, when the slave callback is invoked, it is passed the current event through its *transfer* parameter.

Note: These enumerations are meant to be OR'd together to form a bit mask of events.

typedef struct *_lpi2c_slave_transfer* lpi2c_slave_transfer_t

LPI2C slave transfer structure.

typedef struct *_lpi2c_slave_handle* lpi2c_slave_handle_t

LPI2C slave handle structure.

typedef void (*lpi2c_slave_transfer_callback_t)(LPI2C_Type *base, *lpi2c_slave_transfer_t* *transfer, void *userData)

Slave event callback function pointer type.

This callback is used only for the slave non-blocking transfer API. To install a callback, use the LPI2C_SlaveSetCallback() function after you have created a handle.

Param base
Base address for the LPI2C instance on which the event occurred.

Param transfer
Pointer to transfer descriptor containing values passed to and/or from the callback.

Param userData
Arbitrary pointer-sized value passed from the application.

struct _lpi2c_slave_config

#include <fsl_lpi2c.h> Structure with settings to initialize the LPI2C slave module.

This structure holds configuration settings for the LPI2C slave peripheral. To initialize this structure to reasonable defaults, call the *LPI2C_SlaveGetDefaultConfig()* function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

Public Members

bool enableSlave

Enable slave mode.

uint8_t address0

Slave's 7-bit address.

uint8_t address1

Alternate slave 7-bit address.

lpi2c_slave_address_match_t addressMatchMode

Address matching options.

bool filterDozeEnable
: Enable digital glitch filter in doze mode.

bool filterEnable
: Enable digital glitch filter.

bool enableGeneralCall
: Enable general call address matching.

struct *_lpi2c_slave_config* sclStall
: SCL stall enable options.

bool ignoreAck
: Continue transfers after a NACK is detected.

bool enableReceivedAddressRead
: Enable reading the address received address as the first byte of data.

uint32_t sdaGlitchFilterWidth_ns
: Width in nanoseconds of the digital filter on the SDA signal. Set to 0 to disable.

uint32_t sclGlitchFilterWidth_ns
: Width in nanoseconds of the digital filter on the SCL signal. Set to 0 to disable.

uint32_t dataValidDelay_ns
: Width in nanoseconds of the data valid delay.

uint32_t clockHoldTime_ns
: Width in nanoseconds of the clock hold time.

struct _lpi2c_slave_transfer
: *#include <fsl_lpi2c.h>* LPI2C slave transfer structure.

Public Members

lpi2c_slave_transfer_event_t event
: Reason the callback is being invoked.

uint8_t receivedAddress
: Matching address send by master.

uint8_t *data
: Transfer buffer

size_t dataSize
: Transfer size

status_t completionStatus

Success or error code describing how the transfer completed. Only applies for *kLPI2C_SlaveCompletionEvent*.

size_t transferredCount

Number of bytes actually transferred since start or last repeated start.

struct __lpi2c_slave_handle

#include <fsl_lpi2c.h> LPI2C slave handle structure.

Note: The contents of this structure are private and subject to change.

Public Members

lpi2c_slave_transfer_t transfer

LPI2C slave transfer copy.

bool isBusy

Whether transfer is busy.

bool wasTransmit

Whether the last transfer was a transmit.

uint32_t eventMask

Mask of enabled events.

uint32_t transferredCount

Count of bytes transferred.

lpi2c_slave_transfer_callback_t callback

Callback function called at transfer event.

void *userData

Callback parameter passed to callback.

struct sclStall

Public Members

bool enableAck

Enables SCL clock stretching during slave-transmit address byte(s) and slave-receiver address and data byte(s) to allow software to write the Transmit ACK Register before the ACK or NACK is transmitted. Clock stretching occurs when transmitting the 9th bit. When enableAckSCLStall is enabled, there is no need to set either enableRxDataSCLStall or enableAddressSCLStall.

bool enableTx

Enables SCL clock stretching when the transmit data flag is set during a slave-transmit transfer.

bool enableRx

Enables SCL clock stretching when receive data flag is set during a slave-receive transfer.

bool enableAddress

Enables SCL clock stretching when the address valid flag is asserted.

2.53 LPSPI: Low Power Serial Peripheral Interface

2.54 LPSPI Peripheral driver

void LPSPI_MasterInit(LPSPI_Type *base, const *lpspi_master_config_t* *masterConfig, uint32_t srcClock_Hz)

Initializes the LPSPI master.

Parameters

- base – LPSPI peripheral address.
- masterConfig – Pointer to structure lpspi_master_config_t.
- srcClock_Hz – Module source input clock in Hertz

void LPSPI_MasterGetDefaultConfig(*lpspi_master_config_t* *masterConfig)

Sets the lpspi_master_config_t structure to default values.

This API initializes the configuration structure for *LPSPI_MasterInit()*. The initialized structure can remain unchanged in *LPSPI_MasterInit()*, or can be modified before calling the *LPSPI_MasterInit()*. Example:

```
lpspi_master_config_t masterConfig;
LPSPI_MasterGetDefaultConfig(&masterConfig);
```

Parameters

- masterConfig – pointer to lpspi_master_config_t structure

void LPSPI_SlaveInit(LPSPI_Type *base, const *lpspi_slave_config_t* *slaveConfig)

LPSPI slave configuration.

Parameters

- base – LPSPI peripheral address.
- slaveConfig – Pointer to a structure lpspi_slave_config_t.

void LPSPI_SlaveGetDefaultConfig(*lpspi_slave_config_t* *slaveConfig)

Sets the lpspi_slave_config_t structure to default values.

This API initializes the configuration structure for *LPSPI_SlaveInit()*. The initialized structure can remain unchanged in *LPSPI_SlaveInit()* or can be modified before calling the *LPSPI_SlaveInit()*. Example:

```
lpspi_slave_config_t slaveConfig;
LPSPI_SlaveGetDefaultConfig(&slaveConfig);
```

Parameters

- slaveConfig – pointer to lpspi_slave_config_t structure.

void LPSPI_Deinit(LPSPI_Type *base)

De-initializes the LPSPI peripheral. Call this API to disable the LPSPI clock.

Parameters

- base – LPSPI peripheral address.

void LPSPI_Reset(LPSPI_Type *base)

Restores the LPSPI peripheral to reset state. Note that this function sets all registers to reset state. As a result, the LPSPI module can't work after calling this API.

Parameters

- base – LPSPI peripheral address.

uint32_t LPSPI_GetInstance(LPSPI_Type *base)

Get the LPSPI instance from peripheral base address.

Parameters

- base – LPSPI peripheral base address.

Returns

LPSPI instance.

static inline void LPSPI_Enable(LPSPI_Type *base, bool enable)

Enables the LPSPI peripheral and sets the MCR MDIS to 0.

Parameters

- base – LPSPI peripheral address.
- enable – Pass true to enable module, false to disable module.

static inline uint32_t LPSPI_GetStatusFlags(LPSPI_Type *base)

Gets the LPSPI status flag state.

Parameters

- base – LPSPI peripheral address.

Returns

The LPSPI status(in SR register).

static inline uint8_t LPSPI_GetTxFifoSize(LPSPI_Type *base)

Gets the LPSPI Tx FIFO size.

Parameters

- base – LPSPI peripheral address.

Returns

The LPSPI Tx FIFO size.

static inline uint8_t LPSPI_GetRxFifoSize(LPSPI_Type *base)

Gets the LPSPI Rx FIFO size.

Parameters

- base – LPSPI peripheral address.

Returns
The LPSPI Rx FIFO size.

static inline uint32_t LPSPI_GetTxFifoCount(LPSPI_Type *base)

Gets the LPSPI Tx FIFO count.

Parameters

- base – LPSPI peripheral address.

Returns
The number of words in the transmit FIFO.

static inline uint32_t LPSPI_GetRxFifoCount(LPSPI_Type *base)

Gets the LPSPI Rx FIFO count.

Parameters

- base – LPSPI peripheral address.

Returns
The number of words in the receive FIFO.

static inline void LPSPI_ClearStatusFlags(LPSPI_Type *base, uint32_t statusFlags)

Clears the LPSPI status flag.

This function clears the desired status bit by using a write-1-to-clear. The user passes in the base and the desired status flag bit to clear. The list of status flags is defined in the _lpspi_flags. Example usage:

```
LPSPI_ClearStatusFlags(base, kLPSPI_TxDataRequestFlag|kLPSPI_RxDataReadyFlag);
```

Parameters

- base – LPSPI peripheral address.
- statusFlags – The status flag used from type _lpspi_flags.

static inline uint32_t LPSPI_GetTcr(LPSPI_Type *base)

static inline void LPSPI_EnableInterrupts(LPSPI_Type *base, uint32_t mask)

Enables the LPSPI interrupts.

This function configures the various interrupt masks of the LPSPI. The parameters are base and an interrupt mask. Note that, for Tx fill and Rx FIFO drain requests, enabling the interrupt request disables the DMA request.

```
LPSPI_EnableInterrupts(base, kLPSPI_TxInterruptEnable | kLPSPI_RxInterruptEnable );
```

Parameters

- base – LPSPI peripheral address.
- mask – The interrupt mask; Use the enum _lpspi_interrupt_enable.

static inline void LPSPI_DisableInterrupts(LPSPI_Type *base, uint32_t mask)

Disables the LPSPI interrupts.

```
LPSPI_DisableInterrupts(base, kLPSPI_TxInterruptEnable | kLPSPI_RxInterruptEnable );
```

Parameters

- base – LPSPI peripheral address.
- mask – The interrupt mask; Use the enum _lpspi_interrupt_enable.

static inline void LPSPI_EnableDMA(LPSPI_Type *base, uint32_t mask)

Enables the LPSPI DMA request.

This function configures the Rx and Tx DMA mask of the LPSPI. The parameters are base and a DMA mask.

```
LPSPI_EnableDMA(base, kLPSPI_TxDmaEnable | kLPSPI_RxDmaEnable);
```

Parameters

- base – LPSPI peripheral address.
- mask – The interrupt mask; Use the enum _lpspi_dma_enable.

static inline void LPSPI_DisableDMA(LPSPI_Type *base, uint32_t mask)

Disables the LPSPI DMA request.

This function configures the Rx and Tx DMA mask of the LPSPI. The parameters are base and a DMA mask.

```
SPI_DisableDMA(base, kLPSPI_TxDmaEnable | kLPSPI_RxDmaEnable);
```

Parameters

- base – LPSPI peripheral address.
- mask – The interrupt mask; Use the enum _lpspi_dma_enable.

static inline uint32_t LPSPI_GetTxRegisterAddress(LPSPI_Type *base)

Gets the LPSPI Transmit Data Register address for a DMA operation.

This function gets the LPSPI Transmit Data Register address because this value is needed for the DMA operation. This function can be used for either master or slave mode.

Parameters

- base – LPSPI peripheral address.

Returns

The LPSPI Transmit Data Register address.

static inline uint32_t LPSPI_GetRxRegisterAddress(LPSPI_Type *base)

Gets the LPSPI Receive Data Register address for a DMA operation.

This function gets the LPSPI Receive Data Register address because this value is needed for the DMA operation. This function can be used for either master or slave mode.

Parameters

- base – LPSPI peripheral address.

Returns

The LPSPI Receive Data Register address.

bool LPSPI_CheckTransferArgument(LPSPI_Type *base, *lpspi_transfer_t* *transfer, bool isEdma)

Check the argument for transfer .

Parameters

- base – LPSPI peripheral address.
- transfer – the transfer struct to be used.
- isEdma – True to check for EDMA transfer, false to check interrupt non-blocking transfer

Returns
Return true for right and false for wrong.

static inline void LPSPI_SetMasterSlaveMode(LPSPI_Type *base, *lpspi_master_slave_mode_t* mode)

Configures the LPSPI for either master or slave.

Note that the CFGR1 should only be written when the LPSPI is disabled (LPSPIx_CR_MEN = 0).

Parameters

- base – LPSPI peripheral address.
- mode – Mode setting (master or slave) of type lpspi_master_slave_mode_t.

static inline void LPSPI_SelectTransferPCS(LPSPI_Type *base, *lpspi_which_pcs_t* select)

Configures the peripheral chip select used for the transfer.

Parameters

- base – LPSPI peripheral address.
- select – LPSPI Peripheral Chip Select (PCS) configuration.

static inline void LPSPI_SetPCSContinous(LPSPI_Type *base, bool IsContinous)

Set the PCS signal to continuous or uncontinuous mode.

Note: In master mode, continuous transfer will keep the PCS asserted at the end of the frame size, until a command word is received that starts a new frame. So PCS must be set back to uncontinuous when transfer finishes. In slave mode, when continuous transfer is enabled, the LPSPI will only transmit the first frame size bits, after that the LPSPI will transmit received data back (assuming a 32-bit shift register).

Parameters

- base – LPSPI peripheral address.
- IsContinous – True to set the transfer PCS to continuous mode, false to set to uncontinuous mode.

static inline bool LPSPI_IsMaster(LPSPI_Type *base)

Returns whether the LPSPI module is in master mode.

Parameters

- base – LPSPI peripheral address.

Returns
Returns true if the module is in master mode or false if the module is in slave mode.

static inline void LPSPI_FlushFifo(LPSPI_Type *base, bool flushTxFifo, bool flushRxFifo)

Flushes the LPSPI FIFOs.

Parameters

- base – LPSPI peripheral address.
- flushTxFifo – Flushes (true) the Tx FIFO, else do not flush (false) the Tx FIFO.
- flushRxFifo – Flushes (true) the Rx FIFO, else do not flush (false) the Rx FIFO.

static inline void LPSPI_SetFifoWatermarks(LPSPI_Type *base, uint32_t txWater, uint32_t rxWater)

Sets the transmit and receive FIFO watermark values.

This function allows the user to set the receive and transmit FIFO watermarks. The function does not compare the watermark settings to the FIFO size. The FIFO watermark should not be equal to or greater than the FIFO size. It is up to the higher level driver to make this check.

Parameters

- base – LPSPI peripheral address.
- txWater – The TX FIFO watermark value. Writing a value equal or greater than the FIFO size is truncated.
- rxWater – The RX FIFO watermark value. Writing a value equal or greater than the FIFO size is truncated.

static inline void LPSPI_SetAllPcsPolarity(LPSPI_Type *base, uint32_t mask)

Configures all LPSPI peripheral chip select polarities simultaneously.

Note that the CFGR1 should only be written when the LPSPI is disabled (LPSPIx_CR_MEN = 0).

This is an example: PCS0 and PCS1 set to active low and other PCSs set to active high. Note that the number of PCS is device-specific.

```
LPSPI_SetAllPcsPolarity(base, kLPSPI_Pcs0ActiveLow | kLPSPI_Pcs1ActiveLow);
```

Parameters

- base – LPSPI peripheral address.
- mask – The PCS polarity mask; Use the enum _lpspi_pcs_polarity.

static inline void LPSPI_SetFrameSize(LPSPI_Type *base, uint32_t frameSize)

Configures the frame size.

The minimum frame size is 8-bits and the maximum frame size is 4096-bits. If the frame size is less than or equal to 32-bits, the word size and frame size are identical. If the frame size is greater than 32-bits, the word size is 32-bits for each word except the last (the last word contains the remainder bits if the frame size is not divisible by 32). The minimum word size is 2-bits. A frame size of 33-bits (or similar) is not supported.

Note 1: The transmit command register should be initialized before enabling the LPSPI in slave mode, although the command register does not update until after the LPSPI is enabled. After it is enabled, the transmit command register should only be changed if the LPSPI is idle.

Note 2: The transmit and command FIFO is a combined FIFO that includes both transmit data and command words. That means the TCR register should be written to when the Tx FIFO is not full.

Parameters

- base – LPSPI peripheral address.
- frameSize – The frame size in number of bits.

uint32_t LPSPI_MasterSetBaudRate(LPSPI_Type *base, uint32_t baudRate_Bps, uint32_t srcClock_Hz, uint32_t *tcrPrescaleValue)

Sets the LPSPI baud rate in bits per second.

This function takes in the desired bitsPerSec (baud rate) and calculates the nearest possible baud rate without exceeding the desired baud rate and returns the calculated baud rate

in bits-per-second. It requires the caller to provide the frequency of the module source clock (in Hertz). Note that the baud rate does not go into effect until the Transmit Control Register (TCR) is programmed with the prescale value. Hence, this function returns the prescale tcrPrescaleValue parameter for later programming in the TCR. The higher level peripheral driver should alert the user of an out of range baud rate input.

Note that the LPSPI module must first be disabled before configuring this. Note that the LPSPI module must be configured for master mode before configuring this.

Parameters

- base – LPSPI peripheral address.
- baudRate_Bps – The desired baud rate in bits per second.
- srcClock_Hz – Module source input clock in Hertz.
- tcrPrescaleValue – The TCR prescale value needed to program the TCR.

Returns

The actual calculated baud rate. This function may also return a "0" if the LPSPI is not configured for master mode or if the LPSPI module is not disabled.

void LPSPI_MasterSetDelayScaler(LPSPI_Type *base, uint32_t scaler, *lpspi_delay_type_t* whichDelay)

Manually configures a specific LPSPI delay parameter (module must be disabled to change the delay values).

This function configures the following: SCK to PCS delay, or PCS to SCK delay, or The configurations must occur between the transfer delay.

The delay names are available in type lpspi_delay_type_t.

The user passes the desired delay along with the delay value. This allows the user to directly set the delay values if they have pre-calculated them or if they simply wish to manually increment the value.

Note that the LPSPI module must first be disabled before configuring this. Note that the LPSPI module must be configured for master mode before configuring this.

Parameters

- base – LPSPI peripheral address.
- scaler – The 8-bit delay value 0x00 to 0xFF (255).
- whichDelay – The desired delay to configure, must be of type lpspi_delay_type_t.

uint32_t LPSPI_MasterSetDelayTimes(LPSPI_Type *base, uint32_t delayTimeInNanoSec, *lpspi_delay_type_t* whichDelay, uint32_t srcClock_Hz)

Calculates the delay based on the desired delay input in nanoseconds (module must be disabled to change the delay values).

This function configures the SCK to PCS delay, PCS to SCK delay, or the delay between transfers. The delay names are available in type lpspi_delay_type_t.

The function calculates the value needed for the desired delay parameter and returns the actual calculated delay. An exact delay match may not be possible, in which case the closest match is calculated without going below the desired delay value. If the input exceeds the maximum capability, the maximum supported delay is returned.

Note that the LPSPI module must first be disabled before configuring this. Note that the LPSPI module must be configured for master mode before configuring this.

Parameters

- base – LPSPI peripheral address.

- delayTimeInNanoSec – The desired delay value in nanoseconds.
- whichDelay – The desired delay to configure, must be of type lpspi_delay_type_t.
- srcClock_Hz – Module source input clock in Hertz.

Returns
Actual calculated delay value in nanoseconds.

static inline void LPSPI_WriteData(LPSPI_Type *base, uint32_t data)

Writes data into the transmit data buffer.

This function writes data passed in by the user to the Transmit Data Register (TDR). The user can pass up to 32-bits of data to load into the TDR. If the frame size exceeds 32-bits, the user has to manage sending the data one 32-bit word at a time. Any writes to the TDR result in an immediate push to the transmit FIFO. This function can be used for either master or slave modes.

Parameters

- base – LPSPI peripheral address.
- data – The data word to be sent.

static inline uint32_t LPSPI_ReadData(LPSPI_Type *base)

Reads data from the data buffer.

This function reads the data from the Receive Data Register (RDR). This function can be used for either master or slave mode.

Parameters

- base – LPSPI peripheral address.

Returns
The data read from the data buffer.

void LPSPI_SetDummyData(LPSPI_Type *base, uint8_t dummyData)

Set up the dummy data.

Parameters

- base – LPSPI peripheral address.
- dummyData – Data to be transferred when tx buffer is NULL. Note: This API has no effect when LPSPI in slave interrupt mode, because driver will set the TXMSK bit to 1 if txData is NULL, no data is loaded from transmit FIFO and output pin is tristated.

void LPSPI_MasterTransferCreateHandle(LPSPI_Type *base, *lpspi_master_handle_t* *handle, *lpspi_master_transfer_callback_t* callback, void *userData)

Initializes the LPSPI master handle.

This function initializes the LPSPI handle, which can be used for other LPSPI transactional APIs. Usually, for a specified LPSPI instance, call this API once to get the initialized handle.

Parameters

- base – LPSPI peripheral address.
- handle – LPSPI handle pointer to lpspi_master_handle_t.
- callback – DSPI callback.
- userData – callback function parameter.

status_t LPSPI_MasterTransferBlocking(LPSPI_Type *base, *lpspi_transfer_t* *transfer)

LPSPI master transfer data using a polling method.

This function transfers data using a polling method. This is a blocking function, which does not return until all transfers have been completed.

Note: The transfer data size should be integer multiples of bytesPerFrame if bytesPerFrame is less than or equal to 4. For bytesPerFrame greater than 4: The transfer data size should be equal to bytesPerFrame if the bytesPerFrame is not integer multiples of 4. Otherwise, the transfer data size can be an integer multiple of bytesPerFrame.

Parameters

- base – LPSPI peripheral address.
- transfer – pointer to lpspi_transfer_t structure.

Returns

status of status_t.

status_t LPSPI_MasterTransferNonBlocking(LPSPI_Type *base, *lpspi_master_handle_t* *handle, *lpspi_transfer_t* *transfer)

LPSPI master transfer data using an interrupt method.

This function transfers data using an interrupt method. This is a non-blocking function, which returns right away. When all data is transferred, the callback function is called.

Note: The transfer data size should be integer multiples of bytesPerFrame if bytesPerFrame is less than or equal to 4. For bytesPerFrame greater than 4: The transfer data size should be equal to bytesPerFrame if the bytesPerFrame is not integer multiples of 4. Otherwise, the transfer data size can be an integer multiple of bytesPerFrame.

Parameters

- base – LPSPI peripheral address.
- handle – pointer to lpspi_master_handle_t structure which stores the transfer state.
- transfer – pointer to lpspi_transfer_t structure.

Returns

status of status_t.

status_t LPSPI_MasterTransferGetCount(LPSPI_Type *base, *lpspi_master_handle_t* *handle, size_t *count)

Gets the master transfer remaining bytes.

This function gets the master transfer remaining bytes.

Parameters

- base – LPSPI peripheral address.
- handle – pointer to lpspi_master_handle_t structure which stores the transfer state.
- count – Number of bytes transferred so far by the non-blocking transaction.

Returns

status of status_t.

void LPSPI_MasterTransferAbort(LPSPI_Type *base, *lpspi_master_handle_t* *handle)

LPSPI master abort transfer which uses an interrupt method.

This function aborts a transfer which uses an interrupt method.

Parameters

- base – LPSPI peripheral address.
- handle – pointer to lpspi_master_handle_t structure which stores the transfer state.

void LPSPI_MasterTransferHandleIRQ(LPSPI_Type *base, *lpspi_master_handle_t* *handle)

LPSPI Master IRQ handler function.

This function processes the LPSPI transmit and receive IRQ.

Parameters

- base – LPSPI peripheral address.
- handle – pointer to lpspi_master_handle_t structure which stores the transfer state.

void LPSPI_SlaveTransferCreateHandle(LPSPI_Type *base, *lpspi_slave_handle_t* *handle, *lpspi_slave_transfer_callback_t* callback, void *userData)

Initializes the LPSPI slave handle.

This function initializes the LPSPI handle, which can be used for other LPSPI transactional APIs. Usually, for a specified LPSPI instance, call this API once to get the initialized handle.

Parameters

- base – LPSPI peripheral address.
- handle – LPSPI handle pointer to lpspi_slave_handle_t.
- callback – DSPI callback.
- userData – callback function parameter.

status_t LPSPI_SlaveTransferNonBlocking(LPSPI_Type *base, *lpspi_slave_handle_t* *handle, *lpspi_transfer_t* *transfer)

LPSPI slave transfer data using an interrupt method.

This function transfer data using an interrupt method. This is a non-blocking function, which returns right away. When all data is transferred, the callback function is called.

Note: The transfer data size should be integer multiples of bytesPerFrame if bytesPerFrame is less than or equal to 4. For bytesPerFrame greater than 4: The transfer data size should be equal to bytesPerFrame if the bytesPerFrame is not an integer multiple of 4. Otherwise, the transfer data size can be an integer multiple of bytesPerFrame.

Parameters

- base – LPSPI peripheral address.
- handle – pointer to lpspi_slave_handle_t structure which stores the transfer state.
- transfer – pointer to lpspi_transfer_t structure.

Returns

status of status_t.

status_t LPSPI_SlaveTransferGetCount(LPSPI_Type *base, *lpspi_slave_handle_t* *handle, size_t *count)

Gets the slave transfer remaining bytes.

This function gets the slave transfer remaining bytes.

Parameters

- base – LPSPI peripheral address.
- handle – pointer to lpspi_slave_handle_t structure which stores the transfer state.

- count – Number of bytes transferred so far by the non-blocking transaction.

Returns
status of status_t.

void LPSPI_SlaveTransferAbort(LPSPI_Type *base, *lpspi_slave_handle_t* *handle)

LPSPI slave aborts a transfer which uses an interrupt method.

This function aborts a transfer which uses an interrupt method.

Parameters

- base – LPSPI peripheral address.
- handle – pointer to lpspi_slave_handle_t structure which stores the transfer state.

void LPSPI_SlaveTransferHandleIRQ(LPSPI_Type *base, *lpspi_slave_handle_t* *handle)

LPSPI Slave IRQ handler function.

This function processes the LPSPI transmit and receives an IRQ.

Parameters

- base – LPSPI peripheral address.
- handle – pointer to lpspi_slave_handle_t structure which stores the transfer state.

bool LPSPI_WaitTxFifoEmpty(LPSPI_Type *base)

Wait for tx FIFO to be empty.

This function wait the tx fifo empty

Parameters

- base – LPSPI peripheral address.

Returns
true for the tx FIFO is ready, false is not.

void LPSPI_DriverIRQHandler(uint32_t instance)

LPSPI driver IRQ handler common entry.

This function provides the common IRQ request entry for LPSPI.

Parameters

- instance – LPSPI instance.

FSL_LPSPI_DRIVER_VERSION

LPSPI driver version.

Status for the LPSPI driver.

Values:

enumerator kStatus_LPSPI_Busy

LPSPI transfer is busy.

enumerator kStatus_LPSPI_Error

LPSPI driver error.

enumerator kStatus_LPSPI_Idle
LPSPI is idle.

enumerator kStatus_LPSPI_OutOfRange
LPSPI transfer out Of range.

enumerator kStatus_LPSPI_Timeout
LPSPI timeout polling status flags.

enum _lpspi_flags
LPSPI status flags in SPIx_SR register.
Values:

enumerator kLPSPI_TxDataRequestFlag
Transmit data flag

enumerator kLPSPI_RxDataReadyFlag
Receive data flag

enumerator kLPSPI_WordCompleteFlag
Word Complete flag

enumerator kLPSPI_FrameCompleteFlag
Frame Complete flag

enumerator kLPSPI_TransferCompleteFlag
Transfer Complete flag

enumerator kLPSPI_TransmitErrorFlag
Transmit Error flag (FIFO underrun)

enumerator kLPSPI_ReceiveErrorFlag
Receive Error flag (FIFO overrun)

enumerator kLPSPI_DataMatchFlag
Data Match flag

enumerator kLPSPI_ModuleBusyFlag
Module Busy flag

enumerator kLPSPI_AllStatusFlag
Used for clearing all w1c status flags

enum _lpspi_interrupt_enable
LPSPI interrupt source.
Values:

enumerator kLPSPI_TxInterruptEnable
Transmit data interrupt enable

enumerator kLPSPI_RxInterruptEnable
Receive data interrupt enable

enumerator kLPSPI_WordCompleteInterruptEnable
Word complete interrupt enable

enumerator kLPSPI_FrameCompleteInterruptEnable
Frame complete interrupt enable

enumerator kLPSPI_TransferCompleteInterruptEnable
Transfer complete interrupt enable

enumerator kLPSPI_TransmitErrorInterruptEnable
Transmit error interrupt enable(FIFO underrun)

enumerator kLPSPI_ReceiveErrorInterruptEnable
Receive Error interrupt enable (FIFO overrun)

enumerator kLPSPI_DataMatchInterruptEnable
Data Match interrupt enable

enumerator kLPSPI_AllInterruptEnable
All above interrupts enable.

enum _lpspi_dma_enable
LPSPI DMA source.
Values:

enumerator kLPSPI_TxDmaEnable
Transmit data DMA enable

enumerator kLPSPI_RxDmaEnable
Receive data DMA enable

enum _lpspi_master_slave_mode
LPSPI master or slave mode configuration.
Values:

enumerator kLPSPI_Master
LPSPI peripheral operates in master mode.

enumerator kLPSPI_Slave
LPSPI peripheral operates in slave mode.

enum _lpspi_which_pcs_config

LPSPI Peripheral Chip Select (PCS) configuration (which PCS to configure).

Values:

enumerator kLPSPI_Pcs0

PCS[0]

enumerator kLPSPI_Pcs1

PCS[1]

enumerator kLPSPI_Pcs2

PCS[2]

enumerator kLPSPI_Pcs3

PCS[3]

enum _lpspi_pcs_polarity_config

LPSPI Peripheral Chip Select (PCS) Polarity configuration.

Values:

enumerator kLPSPI_PcsActiveHigh

PCS Active High (idles low)

enumerator kLPSPI_PcsActiveLow

PCS Active Low (idles high)

enum _lpspi_pcs_polarity

LPSPI Peripheral Chip Select (PCS) Polarity.

Values:

enumerator kLPSPI_Pcs0ActiveLow

Pcs0 Active Low (idles high).

enumerator kLPSPI_Pcs1ActiveLow

Pcs1 Active Low (idles high).

enumerator kLPSPI_Pcs2ActiveLow

Pcs2 Active Low (idles high).

enumerator kLPSPI_Pcs3ActiveLow

Pcs3 Active Low (idles high).

enumerator kLPSPI_PcsAllActiveLow

Pcs0 to Pcs5 Active Low (idles high).

enum _lpspi_clock_polarity

LPSPI clock polarity configuration.

Values:

enumerator kLPSPI_ClockPolarityActiveHigh

CPOL=0. Active-high LPSPI clock (idles low)

enumerator kLPSPI_ClockPolarityActiveLow

CPOL=1. Active-low LPSPI clock (idles high)

enum _lpspi_clock_phase

LPSPI clock phase configuration.

Values:

enumerator kLPSPI_ClockPhaseFirstEdge

CPHA=0. Data is captured on the leading edge of the SCK and changed on the following edge.

enumerator kLPSPI_ClockPhaseSecondEdge

CPHA=1. Data is changed on the leading edge of the SCK and captured on the following edge.

enum _lpspi_shift_direction

LPSPI data shifter direction options.

Values:

enumerator kLPSPI_MsbFirst

Data transfers start with most significant bit.

enumerator kLPSPI_LsbFirst

Data transfers start with least significant bit.

enum _lpspi_host_request_select

LPSPI Host Request select configuration.

Values:

enumerator kLPSPI_HostReqExtPin

Host Request is an ext pin.

enumerator kLPSPI_HostReqInternalTrigger

Host Request is an internal trigger.

enum _lpspi_match_config

LPSPI Match configuration options.

Values:

enumerator kLPSI_MatchDisabled

LPSPI Match Disabled.

enumerator kLPSI_1stWordEqualsM0orM1

LPSPI Match Enabled.

enumerator kLPSI_AnyWordEqualsM0orM1
LPSPI Match Enabled.

enumerator kLPSI_1stWordEqualsM0and2ndWordEqualsM1
LPSPI Match Enabled.

enumerator kLPSI_AnyWordEqualsM0andNxtWordEqualsM1
LPSPI Match Enabled.

enumerator kLPSI_1stWordAndM1EqualsM0andM1
LPSPI Match Enabled.

enumerator kLPSI_AnyWordAndM1EqualsM0andM1
LPSPI Match Enabled.

enum _lpspi_pin_config
LPSPI pin (SDO and SDI) configuration.
Values:

enumerator kLPSPI_SdiInSdoOut
LPSPI SDI input, SDO output.

enumerator kLPSPI_SdiInSdiOut
LPSPI SDI input, SDI output.

enumerator kLPSPI_SdoInSdoOut
LPSPI SDO input, SDO output.

enumerator kLPSPI_SdoInSdiOut
LPSPI SDO input, SDI output.

enum _lpspi_data_out_config
LPSPI data output configuration.
Values:

enumerator kLpspiDataOutRetained
Data out retains last value when chip select is de-asserted

enumerator kLpspiDataOutTristate
Data out is tristated when chip select is de-asserted

enum _lpspi_transfer_width
LPSPI transfer width configuration.
Values:

enumerator kLPSPI_SingleBitXfer
1-bit shift at a time, data out on SDO, in on SDI (normal mode)

enumerator kLPSPI_TwoBitXfer
2-bits shift out on SDO/SDI and in on SDO/SDI

enumerator kLPSPI_FourBitXfer
4-bits shift out on SDO/SDI/PCS[3:2] and in on SDO/SDI/PCS[3:2]

enum _lpspi_delay_type
LPSPI delay type selection.
Values:

enumerator kLPSPI_PcsToSck
PCS-to-SCK delay.

enumerator kLPSPI_LastSckToPcs
Last SCK edge to PCS delay.

enumerator kLPSPI_BetweenTransfer
Delay between transfers.

enum _lpspi_transfer_config_flag_for_master
Use this enumeration for LPSPI master transfer configFlags.
Values:

enumerator kLPSPI_MasterPcs0
LPSPI master PCS shift macro , internal used. LPSPI master transfer use PCS0 signal

enumerator kLPSPI_MasterPcs1
LPSPI master PCS shift macro , internal used. LPSPI master transfer use PCS1 signal

enumerator kLPSPI_MasterPcs2
LPSPI master PCS shift macro , internal used. LPSPI master transfer use PCS2 signal

enumerator kLPSPI_MasterPcs3
LPSPI master PCS shift macro , internal used. LPSPI master transfer use PCS3 signal

enumerator kLPSPI_MasterPcsContinuous
Is PCS signal continuous

enumerator kLPSPI_MasterByteSwap
Is master swap the byte. For example, when want to send data 1 2 3 4 5 6 7 8 (suppose you set lpspi_shift_direction_t to MSB).

i. If you set bitPerFrame = 8 , no matter the kLPSPI_MasterByteSwapyou flag is used or not, the waveform is 1 2 3 4 5 6 7 8.
ii. If you set bitPerFrame = 16 : (1) the waveform is 2 1 4 3 6 5 8 7 if you do not use the kLPSPI_MasterByteSwap flag. (2) the waveform is 1 2 3 4 5 6 7 8 if you use the kLPSPI_MasterByteSwap flag.
iii. If you set bitPerFrame = 32 : (1) the waveform is 4 3 2 1 8 7 6 5 if you do not use the kLPSPI_MasterByteSwap flag. (2) the waveform is 1 2 3 4 5 6 7 8 if you use the kLPSPI_MasterByteSwap flag.

enum _lpspi_transfer_config_flag_for_slave

Use this enumeration for LPSPI slave transfer configFlags.

Values:

enumerator kLPSPI_SlavePcs0

LPSPI slave PCS shift macro , internal used. LPSPI slave transfer use PCS0 signal

enumerator kLPSPI_SlavePcs1

LPSPI slave PCS shift macro , internal used. LPSPI slave transfer use PCS1 signal

enumerator kLPSPI_SlavePcs2

LPSPI slave PCS shift macro , internal used. LPSPI slave transfer use PCS2 signal

enumerator kLPSPI_SlavePcs3

LPSPI slave PCS shift macro , internal used. LPSPI slave transfer use PCS3 signal

enumerator kLPSPI_SlaveByteSwap

Is slave swap the byte. For example, when want to send data 1 2 3 4 5 6 7 8 (suppose you set lpspi_shift_direction_t to MSB).

i. If you set bitPerFrame = 8 , no matter the kLPSPI_SlaveByteSwap flag is used or not, the waveform is 1 2 3 4 5 6 7 8.

ii. If you set bitPerFrame = 16 : (1) the waveform is 2 1 4 3 6 5 8 7 if you do not use the kLPSPI_SlaveByteSwap flag. (2) the waveform is 1 2 3 4 5 6 7 8 if you use the kLPSPI_SlaveByteSwap flag.

iii. If you set bitPerFrame = 32 : (1) the waveform is 4 3 2 1 8 7 6 5 if you do not use the kLPSPI_SlaveByteSwap flag. (2) the waveform is 1 2 3 4 5 6 7 8 if you use the kLPSPI_SlaveByteSwap flag.

enum _lpspi_transfer_state

LPSPI transfer state, which is used for LPSPI transactional API state machine.

Values:

enumerator kLPSPI_Idle

Nothing in the transmitter/receiver.

enumerator kLPSPI_Busy

Transfer queue is not finished.

enumerator kLPSPI_Error

Transfer error.

typedef enum *_lpspi_master_slave_mode* lpspi_master_slave_mode_t

LPSPI master or slave mode configuration.

typedef enum *_lpspi_which_pcs_config* lpspi_which_pcs_t

LPSPI Peripheral Chip Select (PCS) configuration (which PCS to configure).

typedef enum *_lpspi_pcs_polarity_config* lpspi_pcs_polarity_config_t
LPSPI Peripheral Chip Select (PCS) Polarity configuration.

typedef enum *_lpspi_clock_polarity* lpspi_clock_polarity_t
LPSPI clock polarity configuration.

typedef enum *_lpspi_clock_phase* lpspi_clock_phase_t
LPSPI clock phase configuration.

typedef enum *_lpspi_shift_direction* lpspi_shift_direction_t
LPSPI data shifter direction options.

typedef enum *_lpspi_host_request_select* lpspi_host_request_select_t
LPSPI Host Request select configuration.

typedef enum *_lpspi_match_config* lpspi_match_config_t
LPSPI Match configuration options.

typedef enum *_lpspi_pin_config* lpspi_pin_config_t
LPSPI pin (SDO and SDI) configuration.

typedef enum *_lpspi_data_out_config* lpspi_data_out_config_t
LPSPI data output configuration.

typedef enum *_lpspi_transfer_width* lpspi_transfer_width_t
LPSPI transfer width configuration.

typedef enum *_lpspi_delay_type* lpspi_delay_type_t
LPSPI delay type selection.

typedef struct *_lpspi_master_config* lpspi_master_config_t
LPSPI master configuration structure.

typedef struct *_lpspi_slave_config* lpspi_slave_config_t
LPSPI slave configuration structure.

typedef struct *_lpspi_master_handle* lpspi_master_handle_t
Forward declaration of the *_lpspi_master_handle* typedefs.

typedef struct *_lpspi_slave_handle* lpspi_slave_handle_t
Forward declaration of the *_lpspi_slave_handle* typedefs.

typedef void (*lpspi_master_transfer_callback_t)(LPSPI_Type *base, *lpspi_master_handle_t* *handle, *status_t* status, void *userData)
Master completion callback function pointer type.

Param base
LPSPI peripheral address.

Param handle
Pointer to the handle for the LPSPI master.

Param status
Success or error code describing whether the transfer is completed.

Param userData
Arbitrary pointer-dataSized value passed from the application.

typedef void (*lpspi_slave_transfer_callback_t)(LPSPI_Type *base, *lpspi_slave_handle_t* *handle, *status_t* status, void *userData)

Slave completion callback function pointer type.

Param base
LPSPI peripheral address.

Param handle
Pointer to the handle for the LPSPI slave.

Param status
Success or error code describing whether the transfer is completed.

Param userData
Arbitrary pointer-dataSized value passed from the application.

typedef struct *_lpspi_transfer* lpspi_transfer_t

LPSPI master/slave transfer structure.

volatile uint8_t g_lpspiDummyData[]

Global variable for dummy data value setting.

LPSPI_DUMMY_DATA

LPSPI dummy data if no Tx data.

Dummy data used for tx if there is not txData.

SPI_RETRY_TIMES

Retry times for waiting flag.

LPSPI_MASTER_PCS_SHIFT

LPSPI master PCS shift macro , internal used.

LPSPI_MASTER_PCS_MASK

LPSPI master PCS shift macro , internal used.

LPSPI_SLAVE_PCS_SHIFT

LPSPI slave PCS shift macro , internal used.

LPSPI_SLAVE_PCS_MASK

LPSPI slave PCS shift macro , internal used.

struct _lpspi_master_config

#include <fsl_lpspi.h> LPSPI master configuration structure.

Public Members

uint32_t baudRate

Baud Rate for LPSPI.

uint32_t bitsPerFrame

Bits per frame, minimum 8, maximum 4096.

lpspi_clock_polarity_t cpol

Clock polarity.

lpspi_clock_phase_t cpha

Clock phase.

lpspi_shift_direction_t direction

MSB or LSB data shift direction.

uint32_t pcsToSckDelayInNanoSec

PCS to SCK delay time in nanoseconds, setting to 0 sets the minimum delay. It sets the boundary value if out of range.

uint32_t lastSckToPcsDelayInNanoSec

Last SCK to PCS delay time in nanoseconds, setting to 0 sets the minimum delay. It sets the boundary value if out of range.

uint32_t betweenTransferDelayInNanoSec

After the SCK delay time with nanoseconds, setting to 0 sets the minimum delay. It sets the boundary value if out of range.

lpspi_which_pcs_t whichPcs

Desired Peripheral Chip Select (PCS).

lpspi_pcs_polarity_config_t pcsActiveHighOrLow

Desired PCS active high or low

lpspi_pin_config_t pinCfg

Configures which pins are used for input and output data during single bit transfers.

lpspi_data_out_config_t dataOutConfig

Configures if the output data is tristated between accesses (LPSPI_PCS is negated).

bool enableInputDelay

Enable master to sample the input data on a delayed SCK. This can help improve slave setup time. Refer to device data sheet for specific time length.

struct __lpspi__slave__config

#include <fsl_lpspi.h> LPSPI slave configuration structure.

Public Members

uint32_t bitsPerFrame
: Bits per frame, minimum 8, maximum 4096.

lpspi_clock_polarity_t cpol
: Clock polarity.

lpspi_clock_phase_t cpha
: Clock phase.

lpspi_shift_direction_t direction
: MSB or LSB data shift direction.

lpspi_which_pcs_t whichPcs
: Desired Peripheral Chip Select (pcs)

lpspi_pcs_polarity_config_t pcsActiveHighOrLow
: Desired PCS active high or low

lpspi_pin_config_t pinCfg
: Configures which pins are used for input and output data during single bit transfers.

lpspi_data_out_config_t dataOutConfig
: Configures if the output data is tristated between accesses (LPSPI_PCS is negated).

struct __lpspi__transfer
: *#include <fsl_lpspi.h>* LPSPI master/slave transfer structure.

Public Members

const uint8_t *txData
: Send buffer.

uint8_t *rxData
: Receive buffer.

volatile size_t dataSize
: Transfer bytes.

uint32_t configFlags
: Transfer transfer configuration flags. Set from _lpspi_transfer_config_flag_for_master if the transfer is used for master or _lpspi_transfer_config_flag_for_slave enumeration if the transfer is used for slave.

struct __lpspi__master__handle
: *#include <fsl_lpspi.h>* LPSPI master transfer handle structure used for transactional API.

Public Members

volatile bool isPcsContinuous
: Is PCS continuous in transfer.

volatile bool writeTcrInIsr
: A flag that whether should write TCR in ISR.

volatile bool isByteSwap
: A flag that whether should byte swap.

volatile bool isTxMask
: A flag that whether TCR[TXMSK] is set.

volatile uint16_t bytesPerFrame
: Number of bytes in each frame

volatile uint16_t frameSize
: Backup of TCR[FRAMESZ]

volatile uint8_t fifoSize
: FIFO dataSize.

volatile uint8_t rxWatermark
: Rx watermark.

volatile uint8_t bytesEachWrite
: Bytes for each write TDR.

volatile uint8_t bytesEachRead
: Bytes for each read RDR.

const uint8_t *volatile txData
: Send buffer.

uint8_t *volatile rxData
: Receive buffer.

volatile size_t txRemainingByteCount
: Number of bytes remaining to send.

volatile size_t rxRemainingByteCount
: Number of bytes remaining to receive.

volatile uint32_t writeRegRemainingTimes
: Write TDR register remaining times.

volatile uint32_t readRegRemainingTimes
: Read RDR register remaining times.

uint32_t totalByteCount
Number of transfer bytes

uint32_t txBuffIfNull
Used if the txData is NULL.

volatile uint8_t state
LPSPI transfer state , _lpspi_transfer_state.

lpspi_master_transfer_callback_t callback
Completion callback.

void *userData
Callback user data.

struct __lpspi_slave_handle
#include <fsl_lpspi.h> LPSPI slave transfer handle structure used for transactional API.

Public Members

volatile bool isByteSwap
A flag that whether should byte swap.

volatile uint8_t fifoSize
FIFO dataSize.

volatile uint8_t rxWatermark
Rx watermark.

volatile uint8_t bytesEachWrite
Bytes for each write TDR.

volatile uint8_t bytesEachRead
Bytes for each read RDR.

const uint8_t *volatile txData
Send buffer.

uint8_t *volatile rxData
Receive buffer.

volatile size_t txRemainingByteCount
Number of bytes remaining to send.

volatile size_t rxRemainingByteCount
Number of bytes remaining to receive.

volatile uint32_t writeRegRemainingTimes
Write TDR register remaining times.

volatile uint32_t readRegRemainingTimes
Read RDR register remaining times.

uint32_t totalByteCount
Number of transfer bytes

volatile uint8_t state
LPSPI transfer state , _lpspi_transfer_state.

volatile uint32_t errorCount
Error count for slave transfer.

lpspi_slave_transfer_callback_t callback
Completion callback.

void *userData
Callback user data.

2.55 LPSPI eDMA Driver

FSL_LPSPI_EDMA_DRIVER_VERSION
LPSPI EDMA driver version.

DMA_MAX_TRANSFER_COUNT
DMA max transfer size.

typedef struct *_lpspi_master_edma_handle* lpspi_master_edma_handle_t
Forward declaration of the *_lpspi_master_edma_handle* typedefs.

typedef struct *_lpspi_slave_edma_handle* lpspi_slave_edma_handle_t
Forward declaration of the *_lpspi_slave_edma_handle* typedefs.

typedef void (*lpspi_master_edma_transfer_callback_t)(LPSPI_Type *base, *lpspi_master_edma_handle_t* *handle, *status_t* status, void *userData)
Completion callback function pointer type.

Param base
LPSPI peripheral base address.

Param handle
Pointer to the handle for the LPSPI master.

Param status
Success or error code describing whether the transfer completed.

Param userData
Arbitrary pointer-dataSized value passed from the application.

typedef void (*lpspi_slave_edma_transfer_callback_t)(LPSPI_Type *base, *lpspi_slave_edma_handle_t* *handle, *status_t* status, void *userData)

Completion callback function pointer type.

Param base
LPSPI peripheral base address.

Param handle
Pointer to the handle for the LPSPI slave.

Param status
Success or error code describing whether the transfer completed.

Param userData
Arbitrary pointer-dataSized value passed from the application.

void LPSPI_MasterTransferCreateHandleEDMA(LPSPI_Type *base, *lpspi_master_edma_handle_t* *handle, *lpspi_master_edma_transfer_callback_t* callback, void *userData, *edma_handle_t* *edmaRxRegToRxDataHandle, *edma_handle_t* *edmaTxDataToTxRegHandle)

Initializes the LPSPI master eDMA handle.

This function initializes the LPSPI eDMA handle which can be used for other LPSPI transactional APIs. Usually, for a specified LPSPI instance, call this API once to get the initialized handle.

Note that the LPSPI eDMA has a separated (Rx and Tx as two sources) or shared (Rx and Tx are the same source) DMA request source. (1) For a separated DMA request source, enable and set the Rx DMAMUX source for edmaRxRegToRxDataHandle and Tx DMAMUX source for edmaTxDataToTxRegHandle. (2) For a shared DMA request source, enable and set the Rx/Tx DMAMUX source for edmaRxRegToRxDataHandle.

Parameters

- base – LPSPI peripheral base address.
- handle – LPSPI handle pointer to lpspi_master_edma_handle_t.
- callback – LPSPI callback.
- userData – callback function parameter.
- edmaRxRegToRxDataHandle – edmaRxRegToRxDataHandle pointer to edma_handle_t.
- edmaTxDataToTxRegHandle – edmaTxDataToTxRegHandle pointer to edma_handle_t.

status_t LPSPI_MasterTransferEDMA(LPSPI_Type *base, *lpspi_master_edma_handle_t* *handle, *lpspi_transfer_t* *transfer)

LPSPI master transfer data using eDMA.

This function transfers data using eDMA. This is a non-blocking function, which returns right away. When all data is transferred, the callback function is called.

Note: The transfer data size should be an integer multiple of bytesPerFrame if bytesPerFrame is less than or equal to 4. For bytesPerFrame greater than 4: The transfer data size should be equal to bytesPerFrame if the bytesPerFrame is not an integer multiple of 4. Otherwise, the transfer data size can be an integer multiple of bytesPerFrame.

Parameters

- base – LPSPI peripheral base address.
- handle – pointer to lpspi_master_edma_handle_t structure which stores the transfer state.

- transfer – pointer to lpspi_transfer_t structure.

Returns
status of status_t.

status_t LPSPI_MasterTransferPrepareEDMALite(LPSPI_Type *base, *lpspi_master_edma_handle_t* *handle, uint32_t configFlags)

LPSPI master config transfer parameter while using eDMA.

This function is preparing to transfer data using eDMA, work with LPSPI_MasterTransferEDMALite.

Parameters

- base – LPSPI peripheral base address.
- handle – pointer to lpspi_master_edma_handle_t structure which stores the transfer state.
- configFlags – transfer configuration flags. *_lpspi_transfer_config_flag_for_master*.

Return values

- kStatus_Success – Execution successfully.
- kStatus_LPSPI_Busy – The LPSPI device is busy.

Returns
Indicates whether LPSPI master transfer was successful or not.

status_t LPSPI_MasterTransferEDMALite(LPSPI_Type *base, *lpspi_master_edma_handle_t* *handle, *lpspi_transfer_t* *transfer)

LPSPI master transfer data using eDMA without configs.

This function transfers data using eDMA. This is a non-blocking function, which returns right away. When all data is transferred, the callback function is called.

Note: This API is only for transfer through DMA without configuration. Before calling this API, you must call LPSPI_MasterTransferPrepareEDMALite to configure it once. The transfer data size should be an integer multiple of bytesPerFrame if bytesPerFrame is less than or equal to 4. For bytesPerFrame greater than 4: The transfer data size should be equal to bytesPerFrame if the bytesPerFrame is not an integer multiple of 4. Otherwise, the transfer data size can be an integer multiple of bytesPerFrame.

Parameters

- base – LPSPI peripheral base address.
- handle – pointer to lpspi_master_edma_handle_t structure which stores the transfer state.
- transfer – pointer to lpspi_transfer_t structure, config field is not uesed.

Return values

- kStatus_Success – Execution successfully.
- kStatus_LPSPI_Busy – The LPSPI device is busy.
- kStatus_InvalidArgument – The transfer structure is invalid.

Returns
Indicates whether LPSPI master transfer was successful or not.

void LPSPI_MasterTransferAbortEDMA(LPSPI_Type *base, *lpspi_master_edma_handle_t* *handle)

LPSPI master aborts a transfer which is using eDMA.

This function aborts a transfer which is using eDMA.

Parameters

- base – LPSPI peripheral base address.
- handle – pointer to lpspi_master_edma_handle_t structure which stores the transfer state.

status_t LPSPI_MasterTransferGetCountEDMA(LPSPI_Type *base, *lpspi_master_edma_handle_t* *handle, size_t *count)

Gets the master eDMA transfer remaining bytes.

This function gets the master eDMA transfer remaining bytes.

Parameters

- base – LPSPI peripheral base address.
- handle – pointer to lpspi_master_edma_handle_t structure which stores the transfer state.
- count – Number of bytes transferred so far by the EDMA transaction.

Returns

status of status_t.

void LPSPI_SlaveTransferCreateHandleEDMA(LPSPI_Type *base, *lpspi_slave_edma_handle_t* *handle, *lpspi_slave_edma_transfer_callback_t* callback, void *userData, *edma_handle_t* *edmaRxRegToRxDataHandle, *edma_handle_t* *edmaTxDataToTxRegHandle)

Initializes the LPSPI slave eDMA handle.

This function initializes the LPSPI eDMA handle which can be used for other LPSPI transactional APIs. Usually, for a specified LPSPI instance, call this API once to get the initialized handle.

Note that LPSPI eDMA has a separated (Rx and Tx as two sources) or shared (Rx and Tx as the same source) DMA request source.

(1) For a separated DMA request source, enable and set the Rx DMAMUX source for edmaRxRegToRxDataHandle and Tx DMAMUX source for edmaTxDataToTxRegHandle. (2) For a shared DMA request source, enable and set the Rx/Rx DMAMUX source for edmaRxRegToRxDataHandle .

Parameters

- base – LPSPI peripheral base address.
- handle – LPSPI handle pointer to lpspi_slave_edma_handle_t.
- callback – LPSPI callback.
- userData – callback function parameter.
- edmaRxRegToRxDataHandle – edmaRxRegToRxDataHandle pointer to edma_handle_t.
- edmaTxDataToTxRegHandle – edmaTxDataToTxRegHandle pointer to edma_handle_t.

status_t LPSPI_SlaveTransferEDMA(LPSPI_Type *base, *lpspi_slave_edma_handle_t* *handle, *lpspi_transfer_t* *transfer)

LPSPI slave transfers data using eDMA.

This function transfers data using eDMA. This is a non-blocking function, which return right away. When all data is transferred, the callback function is called.

Note: The transfer data size should be an integer multiple of bytesPerFrame if bytesPerFrame is less than or equal to 4. For bytesPerFrame greater than 4: The transfer data size

should be equal to bytesPerFrame if the bytesPerFrame is not an integer multiple of 4. Otherwise, the transfer data size can be an integer multiple of bytesPerFrame.

Parameters

- base – LPSPI peripheral base address.
- handle – pointer to lpspi_slave_edma_handle_t structure which stores the transfer state.
- transfer – pointer to lpspi_transfer_t structure.

Returns
status of status_t.

void LPSPI_SlaveTransferAbortEDMA(LPSPI_Type *base, *lpspi_slave_edma_handle_t* *handle)

LPSPI slave aborts a transfer which is using eDMA.

This function aborts a transfer which is using eDMA.

Parameters

- base – LPSPI peripheral base address.
- handle – pointer to lpspi_slave_edma_handle_t structure which stores the transfer state.

status_t LPSPI_SlaveTransferGetCountEDMA(LPSPI_Type *base, *lpspi_slave_edma_handle_t* *handle, size_t *count)

Gets the slave eDMA transfer remaining bytes.

This function gets the slave eDMA transfer remaining bytes.

Parameters

- base – LPSPI peripheral base address.
- handle – pointer to lpspi_slave_edma_handle_t structure which stores the transfer state.
- count – Number of bytes transferred so far by the eDMA transaction.

Returns
status of status_t.

struct __lpspi_master_edma_handle

#include <fsl_lpspi_edma.h> LPSPI master eDMA transfer handle structure used for transactional API.

Public Members

volatile bool isPcsContinuous

Is PCS continuous in transfer.

volatile bool isByteSwap

A flag that whether should byte swap.

volatile uint8_t fifoSize

FIFO dataSize.

volatile uint8_t rxWatermark

Rx watermark.

volatile uint8_t bytesEachWrite
: Bytes for each write TDR.

volatile uint8_t bytesEachRead
: Bytes for each read RDR.

volatile uint8_t bytesLastRead
: Bytes for last read RDR.

volatile bool isThereExtraRxBytes
: Is there extra RX byte.

const uint8_t *volatile txData
: Send buffer.

uint8_t *volatile rxData
: Receive buffer.

volatile size_t txRemainingByteCount
: Number of bytes remaining to send.

volatile size_t rxRemainingByteCount
: Number of bytes remaining to receive.

volatile uint32_t writeRegRemainingTimes
: Write TDR register remaining times.

volatile uint32_t readRegRemainingTimes
: Read RDR register remaining times.

uint32_t totalByteCount
: Number of transfer bytes

edma_tcd_t *lastTimeTCD
: Pointer to the lastTime TCD

bool isMultiDMATransmit
: Is there multi DMA transmit

volatile uint8_t dmaTransmitTime
: DMA Transfer times.

uint32_t lastTimeDataBytes
: DMA transmit last Time data Bytes

uint32_t dataBytesEveryTime
: Bytes in a time for DMA transfer, default is DMA_MAX_TRANSFER_COUNT

edma_transfer_config_t transferConfigRx
Config of DMA rx channel.

edma_transfer_config_t transferConfigTx
Config of DMA tx channel.

uint32_t txBuffIfNull
Used if there is not txData for DMA purpose.

uint32_t rxBuffIfNull
Used if there is not rxData for DMA purpose.

uint32_t transmitCommand
Used to write TCR for DMA purpose.

volatile uint8_t state
LPSPI transfer state , _lpspi_transfer_state.

uint8_t nbytes
eDMA minor byte transfer count initially configured.

lpspi_master_edma_transfer_callback_t callback
Completion callback.

void *userData
Callback user data.

edma_handle_t *edmaRxRegToRxDataHandle
edma_handle_t handle point used for RxReg to RxData buff

edma_handle_t *edmaTxDataToTxRegHandle
edma_handle_t handle point used for TxData to TxReg buff

edma_tcd_t lpspiSoftwareTCD[3]
SoftwareTCD, internal used

struct __lpspi_slave_edma_handle
#include <fsl_lpspi_edma.h> LPSPI slave eDMA transfer handle structure used for transactional API.

Public Members

volatile bool isByteSwap
A flag that whether should byte swap.

volatile uint8_t fifoSize
FIFO dataSize.

volatile uint8_t rxWatermark
: Rx watermark.

volatile uint8_t bytesEachWrite
: Bytes for each write TDR.

volatile uint8_t bytesEachRead
: Bytes for each read RDR.

volatile uint8_t bytesLastRead
: Bytes for last read RDR.

volatile bool isThereExtraRxBytes
: Is there extra RX byte.

uint8_t nbytes
: eDMA minor byte transfer count initially configured.

const uint8_t *volatile txData
: Send buffer.

uint8_t *volatile rxData
: Receive buffer.

volatile size_t txRemainingByteCount
: Number of bytes remaining to send.

volatile size_t rxRemainingByteCount
: Number of bytes remaining to receive.

volatile uint32_t writeRegRemainingTimes
: Write TDR register remaining times.

volatile uint32_t readRegRemainingTimes
: Read RDR register remaining times.

uint32_t totalByteCount
: Number of transfer bytes

uint32_t txBuffIfNull
: Used if there is not txData for DMA purpose.

uint32_t rxBuffIfNull
: Used if there is not rxData for DMA purpose.

volatile uint8_t state
: LPSPI transfer state.

uint32_t errorCount
Error count for slave transfer.

lpspi_slave_edma_transfer_callback_t callback
Completion callback.

void *userData
Callback user data.

edma_handle_t *edmaRxRegToRxDataHandle
edma_handle_t handle point used for RxReg to RxData buff

edma_handle_t *edmaTxDataToTxRegHandle
edma_handle_t handle point used for TxData to TxReg

edma_tcd_t lpspiSoftwareTCD[2]
SoftwareTCD, internal used

2.56 LPTMR: Low-Power Timer

void LPTMR_Init(LPTMR_Type *base, const *lptmr_config_t* *config)
Ungates the LPTMR clock and configures the peripheral for a basic operation.

Note: This API should be called at the beginning of the application using the LPTMR driver.

Parameters

- base – LPTMR peripheral base address
- config – A pointer to the LPTMR configuration structure.

void LPTMR_Deinit(LPTMR_Type *base)
Gates the LPTMR clock.

Parameters

- base – LPTMR peripheral base address

void LPTMR_GetDefaultConfig(*lptmr_config_t* *config)
Fills in the LPTMR configuration structure with default settings.

The default values are as follows.

```
config->timerMode = kLPTMR_TimerModeTimeCounter;
config->pinSelect = kLPTMR_PinSelectInput_0;
config->pinPolarity = kLPTMR_PinPolarityActiveHigh;
config->enableFreeRunning = false;
config->bypassPrescaler = true;
config->prescalerClockSource = kLPTMR_PrescalerClock_1;
config->value = kLPTMR_Prescale_Glitch_0;
```

Parameters

- config – A pointer to the LPTMR configuration structure.

static inline void LPTMR_EnableInterrupts(LPTMR_Type *base, uint32_t mask)

Enables the selected LPTMR interrupts.

Parameters

- base – LPTMR peripheral base address
- mask – The interrupts to enable. This is a logical OR of members of the enumeration *lptmr_interrupt_enable_t*

static inline void LPTMR_DisableInterrupts(LPTMR_Type *base, uint32_t mask)

Disables the selected LPTMR interrupts.

Parameters

- base – LPTMR peripheral base address
- mask – The interrupts to disable. This is a logical OR of members of the enumeration *lptmr_interrupt_enable_t*.

static inline uint32_t LPTMR_GetEnabledInterrupts(LPTMR_Type *base)

Gets the enabled LPTMR interrupts.

Parameters

- base – LPTMR peripheral base address

Returns

The enabled interrupts. This is the logical OR of members of the enumeration *lptmr_interrupt_enable_t*

static inline uint32_t LPTMR_GetStatusFlags(LPTMR_Type *base)

Gets the LPTMR status flags.

Parameters

- base – LPTMR peripheral base address

Returns

The status flags. This is the logical OR of members of the enumeration *lptmr_status_flags_t*

static inline void LPTMR_ClearStatusFlags(LPTMR_Type *base, uint32_t mask)

Clears the LPTMR status flags.

Parameters

- base – LPTMR peripheral base address
- mask – The status flags to clear. This is a logical OR of members of the enumeration *lptmr_status_flags_t*.

static inline void LPTMR_SetTimerPeriod(LPTMR_Type *base, uint32_t ticks)

Sets the timer period in units of count.

Timers counts from 0 until it equals the count value set here. The count value is written to the CMR register.

Note:

a. The TCF flag is set with the CNR equals the count provided here and then increments.

b. Call the utility macros provided in the fsl_common.h to convert to ticks.

Parameters

- base – LPTMR peripheral base address

- ticks – A timer period in units of ticks

static inline uint32_t LPTMR_GetCurrentTimerCount(LPTMR_Type *base)

Reads the current timer counting value.

This function returns the real-time timer counting value in a range from 0 to a timer period.

Note: Call the utility macros provided in the fsl_common.h to convert ticks to usec or msec.

Parameters

- base – LPTMR peripheral base address

Returns

The current counter value in ticks

static inline void LPTMR_StartTimer(LPTMR_Type *base)

Starts the timer.

After calling this function, the timer counts up to the CMR register value. Each time the timer reaches the CMR value and then increments, it generates a trigger pulse and sets the timeout interrupt flag. An interrupt is also triggered if the timer interrupt is enabled.

Parameters

- base – LPTMR peripheral base address

static inline void LPTMR_StopTimer(LPTMR_Type *base)

Stops the timer.

This function stops the timer and resets the timer's counter register.

Parameters

- base – LPTMR peripheral base address

FSL_LPTMR_DRIVER_VERSION

Driver Version

enum _lptmr_pin_select

LPTMR pin selection used in pulse counter mode.

Values:

enumerator kLPTMR_PinSelectInput_0

Pulse counter input 0 is selected

enumerator kLPTMR_PinSelectInput_1

Pulse counter input 1 is selected

enumerator kLPTMR_PinSelectInput_2

Pulse counter input 2 is selected

enumerator kLPTMR_PinSelectInput_3

Pulse counter input 3 is selected

enum _lptmr_pin_polarity

LPTMR pin polarity used in pulse counter mode.

Values:

enumerator kLPTMR_PinPolarityActiveHigh

Pulse Counter input source is active-high

enumerator kLPTMR_PinPolarityActiveLow

Pulse Counter input source is active-low

enum _lptmr_timer_mode

LPTMR timer mode selection.

Values:

enumerator kLPTMR_TimerModeTimeCounter

Time Counter mode

enumerator kLPTMR_TimerModePulseCounter

Pulse Counter mode

enum _lptmr_prescaler_glitch_value

LPTMR prescaler/glitch filter values.

Values:

enumerator kLPTMR_Prescale_Glitch_0

Prescaler divide 2, glitch filter does not support this setting

enumerator kLPTMR_Prescale_Glitch_1

Prescaler divide 4, glitch filter 2

enumerator kLPTMR_Prescale_Glitch_2

Prescaler divide 8, glitch filter 4

enumerator kLPTMR_Prescale_Glitch_3

Prescaler divide 16, glitch filter 8

enumerator kLPTMR_Prescale_Glitch_4

Prescaler divide 32, glitch filter 16

enumerator kLPTMR_Prescale_Glitch_5

Prescaler divide 64, glitch filter 32

enumerator kLPTMR_Prescale_Glitch_6

Prescaler divide 128, glitch filter 64

enumerator kLPTMR_Prescale_Glitch_7

Prescaler divide 256, glitch filter 128

enumerator kLPTMR_Prescale_Glitch_8
Prescaler divide 512, glitch filter 256

enumerator kLPTMR_Prescale_Glitch_9
Prescaler divide 1024, glitch filter 512

enumerator kLPTMR_Prescale_Glitch_10
Prescaler divide 2048 glitch filter 1024

enumerator kLPTMR_Prescale_Glitch_11
Prescaler divide 4096, glitch filter 2048

enumerator kLPTMR_Prescale_Glitch_12
Prescaler divide 8192, glitch filter 4096

enumerator kLPTMR_Prescale_Glitch_13
Prescaler divide 16384, glitch filter 8192

enumerator kLPTMR_Prescale_Glitch_14
Prescaler divide 32768, glitch filter 16384

enumerator kLPTMR_Prescale_Glitch_15
Prescaler divide 65536, glitch filter 32768

enum _lptmr_prescaler_clock_select
LPTMR prescaler/glitch filter clock select.

Note: Clock connections are SoC-specific

Values:

enum _lptmr_interrupt_enable
List of the LPTMR interrupts.
Values:

enumerator kLPTMR_TimerInterruptEnable
Timer interrupt enable

enum _lptmr_status_flags
List of the LPTMR status flags.
Values:

enumerator kLPTMR_TimerCompareFlag
Timer compare flag

typedef enum *_lptmr_pin_select* lptmr_pin_select_t
LPTMR pin selection used in pulse counter mode.

typedef enum *_lptmr_pin_polarity* lptmr_pin_polarity_t

LPTMR pin polarity used in pulse counter mode.

typedef enum *_lptmr_timer_mode* lptmr_timer_mode_t

LPTMR timer mode selection.

typedef enum *_lptmr_prescaler_glitch_value* lptmr_prescaler_glitch_value_t

LPTMR prescaler/glitch filter values.

typedef enum *_lptmr_prescaler_clock_select* lptmr_prescaler_clock_select_t

LPTMR prescaler/glitch filter clock select.

Note: Clock connections are SoC-specific

---

typedef enum *_lptmr_interrupt_enable* lptmr_interrupt_enable_t

List of the LPTMR interrupts.

typedef enum *_lptmr_status_flags* lptmr_status_flags_t

List of the LPTMR status flags.

typedef struct *_lptmr_config* lptmr_config_t

LPTMR config structure.

This structure holds the configuration settings for the LPTMR peripheral. To initialize this structure to reasonable defaults, call the *LPTMR_GetDefaultConfig()* function and pass a pointer to your configuration structure instance.

The configuration struct can be made constant so it resides in flash.

static inline void LPTMR_EnableTimerDMA(LPTMR_Type *base, bool enable)

Enable or disable timer DMA request.

Toggles CSR[TDRE] on the LPTMR side only: when enabled, every compare event (CSR[TCF]=1) raises an LPTMR DMA request line which is auto-cleared after the DMA controller services it.

Note: LPTMR runs on a low-power clock that is asynchronous to the EDMA bus clock. On some EDMA IP variants the channel has TWO gates that must BOTH be opened for an LPTMR request to be accepted: the base hardware request gate (ERQ, opened by *EDMA_EnableChannelRequest()*) and an extra asynchronous-request gate (opened by *EDMA_EnableAsyncRequest()* on EDMA4; the classic EDMA + DMAMUX combination does not need this).

Parameters

- base – base LPTMR peripheral base address
- enable – Switcher of timer DMA feature. “true” means to enable, “false” means to disable.

struct _lptmr_config

#include <fsl_lptmr.h> LPTMR config structure.

This structure holds the configuration settings for the LPTMR peripheral. To initialize this structure to reasonable defaults, call the *LPTMR_GetDefaultConfig()* function and pass a pointer to your configuration structure instance.

The configuration struct can be made constant so it resides in flash.

Public Members

lptmr_timer_mode_t timerMode

Time counter mode or pulse counter mode

lptmr_pin_select_t pinSelect

LPTMR pulse input pin select; used only in pulse counter mode

lptmr_pin_polarity_t pinPolarity

LPTMR pulse input pin polarity; used only in pulse counter mode

bool enableFreeRunning

True: enable free running, counter is reset on overflow False: counter is reset when the compare flag is set

bool bypassPrescaler

True: bypass prescaler; false: use clock from prescaler

lptmr_prescaler_clock_select_t prescalerClockSource

LPTMR clock source

lptmr_prescaler_glitch_value_t value

Prescaler or glitch filter value

2.57 LPUART: Low Power Universal Asynchronous Receiver/Transmitter Driver

2.58 LPUART Driver

static inline void LPUART_SoftwareReset(LPUART_Type *base)

Resets the LPUART using software.

This function resets all internal logic and registers except the Global Register. Remains set until cleared by software.

Parameters

- base – LPUART peripheral base address.

status_t LPUART_Init(LPUART_Type *base, const *lpuart_config_t* *config, uint32_t srcClock_Hz)

Initializes an LPUART instance with the user configuration structure and the peripheral clock.

This function configures the LPUART module with user-defined settings. Call the *LPUART_GetDefaultConfig()* function to configure the configuration structure and get the

default configuration. The example below shows how to use this API to configure the LPUART.

```
lpuart_config_t lpuartConfig;
lpuartConfig.baudRate_Bps = 115200U;
lpuartConfig.parityMode = kLPUART_ParityDisabled;
lpuartConfig.dataBitsCount = kLPUART_EightDataBits;
lpuartConfig.isMsb = false;
lpuartConfig.stopBitCount = kLPUART_OneStopBit;
lpuartConfig.txFifoWatermark = 0;
lpuartConfig.rxFifoWatermark = 1;
LPUART_Init(LPUART1, &lpuartConfig, 20000000U);
```

Parameters

- base – LPUART peripheral base address.
- config – Pointer to a user-defined configuration structure.
- srcClock_Hz – LPUART clock source frequency in HZ.

Return values

- kStatus_LPUART_BaudrateNotSupport – Baudrate is not support in current clock source.
- kStatus_Success – LPUART initialize succeed

status_t LPUART_Deinit(LPUART_Type *base)

Deinitializes a LPUART instance.

This function waits for transmit to complete, disables TX and RX, and disables the LPUART clock.

Parameters

- base – LPUART peripheral base address.

Return values

- kStatus_Success – Deinit is success.
- kStatus_LPUART_Timeout – Timeout during deinit.

void LPUART_GetDefaultConfig(*lpuart_config_t* *config)

Gets the default configuration structure.

This function initializes the LPUART configuration structure to a default value. The default values are: lpuartConfig->baudRate_Bps = 115200U; lpuartConfig->parityMode = kLPUART_ParityDisabled; lpuartConfig->dataBitsCount = kLPUART_EightDataBits; lpuartConfig->isMsb = false; lpuartConfig->stopBitCount = kLPUART_OneStopBit; lpuartConfig->txFifoWatermark = 0; lpuartConfig->rxFifoWatermark = 1; lpuartConfig->rxIdleType = kLPUART_IdleTypeStartBit; lpuartConfig->rxIdleConfig = kLPUART_IdleCharacter1; lpuartConfig->enableTx = false; lpuartConfig->enableRx = false;

Parameters

- config – Pointer to a configuration structure.

status_t LPUART_SetBaudRate(LPUART_Type *base, uint32_t baudRate_Bps, uint32_t srcClock_Hz)

Sets the LPUART instance baudrate.

This function configures the LPUART module baudrate. This function is used to update the LPUART module baudrate after the LPUART module is initialized by the LPUART_Init.

```
LPUART_SetBaudRate(LPUART1, 115200U, 20000000U);
```

Parameters

- base – LPUART peripheral base address.
- baudRate_Bps – LPUART baudrate to be set.
- srcClock_Hz – LPUART clock source frequency in HZ.

Return values

- kStatus_LPUART_BaudrateNotSupport – Baudrate is not supported in the current clock source.
- kStatus_Success – Set baudrate succeeded.

void LPUART_Enable9bitMode(LPUART_Type *base, bool enable)

Enable 9-bit data mode for LPUART.

This function set the 9-bit mode for LPUART module. The 9th bit is not used for parity thus can be modified by user.

Parameters

- base – LPUART peripheral base address.
- enable – true to enable, flase to disable.

static inline void LPUART_SetMatchAddress(LPUART_Type *base, uint16_t address1, uint16_t address2)

Set the LPUART address.

This function configures the address for LPUART module that works as slave in 9-bit data mode. One or two address fields can be configured. When the address field's match enable bit is set, the frame it receices with MSB being 1 is considered as an address frame, otherwise it is considered as data frame. Once the address frame matches one of slave's own addresses, this slave is addressed. This address frame and its following data frames are stored in the receive buffer, otherwise the frames will be discarded. To un-address a slave, just send an address frame with unmatched address.

Note: Any LPUART instance joined in the multi-slave system can work as slave. The position of the address mark is the same as the parity bit when parity is enabled for 8 bit and 9 bit data formats.

Parameters

- base – LPUART peripheral base address.
- address1 – LPUART slave address1.
- address2 – LPUART slave address2.

static inline void LPUART_EnableMatchAddress(LPUART_Type *base, bool match1, bool match2)

Enable the LPUART match address feature.

Parameters

- base – LPUART peripheral base address.
- match1 – true to enable match address1, false to disable.
- match2 – true to enable match address2, false to disable.

static inline void LPUART_SetRxFifoWatermark(LPUART_Type *base, uint8_t water)

Sets the rx FIFO watermark.

Parameters

- base – LPUART peripheral base address.
- water – Rx FIFO watermark.

static inline void LPUART_SetTxFifoWatermark(LPUART_Type *base, uint8_t water)

Sets the tx FIFO watermark.

Parameters

- base – LPUART peripheral base address.
- water – Tx FIFO watermark.

static inline void LPUART_TransferEnable16Bit(*lpuart_handle_t* *handle, bool enable)

Sets the LPUART using 16bit transmit, only for 9bit or 10bit mode.

This function Enable 16bit Data transmit in lpuart_handle_t.

Parameters

- handle – LPUART handle pointer.
- enable – true to enable, false to disable.

uint32_t LPUART_GetStatusFlags(LPUART_Type *base)

Gets LPUART status flags.

This function gets all LPUART status flags. The flags are returned as the logical OR value of the enumerators *_lpuart_flags*. To check for a specific status, compare the return value with enumerators in the *_lpuart_flags*. For example, to check whether the TX is empty:

```
if (kLPUART_TxDataRegEmptyFlag & LPUART_GetStatusFlags(LPUART1))
{
    ...
}
```

Parameters

- base – LPUART peripheral base address.

Returns

LPUART status flags which are ORed by the enumerators in the _lpuart_flags.

status_t LPUART_ClearStatusFlags(LPUART_Type *base, uint32_t mask)

Clears status flags with a provided mask.

This function clears LPUART status flags with a provided mask. Automatically cleared flags can't be cleared by this function. Flags that can only cleared or set by hardware are: kLPUART_TxDataRegEmptyFlag, kLPUART_TransmissionCompleteFlag, kLPUART_RxDataRegFullFlag, kLPUART_RxActiveFlag, kLPUART_NoiseErrorFlag, kLPUART_ParityErrorFlag, kLPUART_TxFifoEmptyFlag,kLPUART_RxFifoEmptyFlag Note: This API should be called when the Tx/Rx is idle, otherwise it takes no effects.

Parameters

- base – LPUART peripheral base address.
- mask – the status flags to be cleared. The user can use the enumerators in the _lpuart_status_flag_t to do the OR operation and get the mask.

Return values

- kStatus_LPUART_FlagCannotClearManually – The flag can't be cleared by this function but it is cleared automatically by hardware.
- kStatus_Success – Status in the mask are cleared.

Returns

0 succeed, others failed.

void LPUART_EnableInterrupts(LPUART_Type *base, uint32_t mask)

Enables LPUART interrupts according to a provided mask.

This function enables the LPUART interrupts according to a provided mask. The mask is a logical OR of enumeration members. See the *_lpuart_interrupt_enable*. This examples shows how to enable TX empty interrupt and RX full interrupt:

```
LPUART_EnableInterrupts(LPUART1,kLPUART_TxDataRegEmptyInterruptEnable | kLPUART_
↪RxDataRegFullInterruptEnable);
```

Parameters

- base – LPUART peripheral base address.
- mask – The interrupts to enable. Logical OR of *_lpuart_interrupt_enable*.

void LPUART_DisableInterrupts(LPUART_Type *base, uint32_t mask)

Disables LPUART interrupts according to a provided mask.

This function disables the LPUART interrupts according to a provided mask. The mask is a logical OR of enumeration members. See *_lpuart_interrupt_enable*. This example shows how to disable the TX empty interrupt and RX full interrupt:

```
LPUART_DisableInterrupts(LPUART1,kLPUART_TxDataRegEmptyInterruptEnable | kLPUART_
↪RxDataRegFullInterruptEnable);
```

Parameters

- base – LPUART peripheral base address.
- mask – The interrupts to disable. Logical OR of *_lpuart_interrupt_enable*.

uint32_t LPUART_GetEnabledInterrupts(LPUART_Type *base)

Gets enabled LPUART interrupts.

This function gets the enabled LPUART interrupts. The enabled interrupts are returned as the logical OR value of the enumerators *_lpuart_interrupt_enable*. To check a specific interrupt enable status, compare the return value with enumerators in *_lpuart_interrupt_enable*. For example, to check whether the TX empty interrupt is enabled:

```
uint32_t enabledInterrupts = LPUART_GetEnabledInterrupts(LPUART1);

if (kLPUART_TxDataRegEmptyInterruptEnable & enabledInterrupts)
{
    ...
}
```

Parameters

- base – LPUART peripheral base address.

Returns

LPUART interrupt flags which are logical OR of the enumerators in *_lpuart_interrupt_enable*.

static inline uintptr_t LPUART_GetDataRegisterAddress(LPUART_Type *base)

Gets the LPUART data register address.

This function returns the LPUART data register address, which is mainly used by the DMA/eDMA.

Parameters

- base – LPUART peripheral base address.

Returns

LPUART data register addresses which are used both by the transmitter and receiver.

static inline void LPUART_EnableTxDMA(LPUART_Type *base, bool enable)

Enables or disables the LPUART transmitter DMA request.

This function enables or disables the transmit data register empty flag, STAT[TDRE], to generate DMA requests.

Parameters

- base – LPUART peripheral base address.
- enable – True to enable, false to disable.

static inline void LPUART_EnableRxDMA(LPUART_Type *base, bool enable)

Enables or disables the LPUART receiver DMA.

This function enables or disables the receiver data register full flag, STAT[RDRF], to generate DMA requests.

Parameters

- base – LPUART peripheral base address.
- enable – True to enable, false to disable.

uint32_t LPUART_GetInstance(LPUART_Type *base)

Get the LPUART instance from peripheral base address.

Parameters

- base – LPUART peripheral base address.

Returns

LPUART instance.

static inline void LPUART_EnableTx(LPUART_Type *base, bool enable)

Enables or disables the LPUART transmitter.

This function enables or disables the LPUART transmitter.

Parameters

- base – LPUART peripheral base address.
- enable – True to enable, false to disable.

static inline void LPUART_EnableRx(LPUART_Type *base, bool enable)

Enables or disables the LPUART receiver.

This function enables or disables the LPUART receiver.

Parameters

- base – LPUART peripheral base address.
- enable – True to enable, false to disable.

static inline void LPUART_WriteByte(LPUART_Type *base, uint8_t data)

Writes to the transmitter register.

This function writes data to the transmitter register directly. The upper layer must ensure that the TX register is empty or that the TX FIFO has room before calling this function.

Parameters

- base – LPUART peripheral base address.
- data – Data write to the TX register.

static inline uint8_t LPUART_ReadByte(LPUART_Type *base)

Reads the receiver register.

This function reads data from the receiver register directly. The upper layer must ensure that the receiver register is full or that the RX FIFO has data before calling this function.

Parameters

- base – LPUART peripheral base address.

Returns

Data read from data register.

static inline uint8_t LPUART_GetRxFifoCount(LPUART_Type *base)

Gets the rx FIFO data count.

Parameters

- base – LPUART peripheral base address.

Returns

rx FIFO data count.

static inline uint8_t LPUART_GetTxFifoCount(LPUART_Type *base)

Gets the tx FIFO data count.

Parameters

- base – LPUART peripheral base address.

Returns

tx FIFO data count.

void LPUART_SendAddress(LPUART_Type *base, uint8_t address)

Transmit an address frame in 9-bit data mode.

Parameters

- base – LPUART peripheral base address.
- address – LPUART slave address.

status_t LPUART_WriteBlocking(LPUART_Type *base, const uint8_t *data, size_t length)

Writes to the transmitter register using a blocking method.

This function polls the transmitter register, first waits for the register to be empty or TX FIFO to have room, and writes data to the transmitter buffer, then waits for the dat to be sent out to the bus.

Parameters

- base – LPUART peripheral base address.
- data – Start address of the data to write.
- length – Size of the data to write.

Return values

- kStatus_LPUART_Timeout – Transmission timed out and was aborted.
- kStatus_Success – Successfully wrote all data.

status_t LPUART_WriteBlocking16bit(LPUART_Type *base, const uint16_t *data, size_t length)

Writes to the transmitter register using a blocking method in 9bit or 10bit mode.

Note: This function only support 9bit or 10bit transfer. Please make sure only 10bit of data is valid and other bits are 0.

Parameters

- base – LPUART peripheral base address.
- data – Start address of the data to write.
- length – Size of the data to write.

Return values

- kStatus_LPUART_Timeout – Transmission timed out and was aborted.
- kStatus_Success – Successfully wrote all data.

status_t LPUART_ReadBlocking(LPUART_Type *base, uint8_t *data, size_t length)

Reads the receiver data register using a blocking method.

This function polls the receiver register, waits for the receiver register full or receiver FIFO has data, and reads data from the TX register.

Parameters

- base – LPUART peripheral base address.
- data – Start address of the buffer to store the received data.
- length – Size of the buffer.

Return values

- kStatus_LPUART_RxHardwareOverrun – Receiver overrun happened while receiving data.
- kStatus_LPUART_NoiseError – Noise error happened while receiving data.
- kStatus_LPUART_FramingError – Framing error happened while receiving data.
- kStatus_LPUART_ParityError – Parity error happened while receiving data.
- kStatus_LPUART_Timeout – Transmission timed out and was aborted.
- kStatus_Success – Successfully received all data.

status_t LPUART_ReadBlocking16bit(LPUART_Type *base, uint16_t *data, size_t length)

Reads the receiver data register in 9bit or 10bit mode.

Note: This function only support 9bit or 10bit transfer.

Parameters

- base – LPUART peripheral base address.
- data – Start address of the buffer to store the received data by 16bit, only 10bit is valid.

- length – Size of the buffer.

Return values

- kStatus_LPUART_RxHardwareOverrun – Receiver overrun happened while receiving data.
- kStatus_LPUART_NoiseError – Noise error happened while receiving data.
- kStatus_LPUART_FramingError – Framing error happened while receiving data.
- kStatus_LPUART_ParityError – Parity error happened while receiving data.
- kStatus_LPUART_Timeout – Transmission timed out and was aborted.
- kStatus_Success – Successfully received all data.

void LPUART_TransferCreateHandle(LPUART_Type *base, *lpuart_handle_t* *handle, *lpuart_transfer_callback_t* callback, void *userData)

Initializes the LPUART handle.

This function initializes the LPUART handle, which can be used for other LPUART transactional APIs. Usually, for a specified LPUART instance, call this API once to get the initialized handle.

The LPUART driver supports the "background" receiving, which means that user can set up an RX ring buffer optionally. Data received is stored into the ring buffer even when the user doesn't call the *LPUART_TransferReceiveNonBlocking()* API. If there is already data received in the ring buffer, the user can get the received data from the ring buffer directly. The ring buffer is disabled if passing NULL as ringBuffer.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.
- callback – Callback function.
- userData – User data.

status_t LPUART_TransferSendNonBlocking(LPUART_Type *base, *lpuart_handle_t* *handle, *lpuart_transfer_t* *xfer)

Transmits a buffer of data using the interrupt method.

This function send data using an interrupt method. This is a non-blocking function, which returns directly without waiting for all data written to the transmitter register. When all data is written to the TX register in the ISR, the LPUART driver calls the callback function and passes the *kStatus_LPUART_TxIdle* as status parameter.

Note: The kStatus_LPUART_TxIdle is passed to the upper layer when all data are written to the TX register. However, there is no check to ensure that all the data sent out. Before disabling the TX, check the kLPUART_TransmissionCompleteFlag to ensure that the transmit is finished.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.
- xfer – LPUART transfer structure, see *lpuart_transfer_t*.

Return values

- kStatus_Success – Successfully start the data transmission.
- kStatus_LPUART_TxBusy – Previous transmission still not finished, data not all written to the TX register.
- kStatus_InvalidArgument – Invalid argument.

void LPUART_TransferStartRingBuffer(LPUART_Type *base, *lpuart_handle_t* *handle, uint8_t *ringBuffer, size_t ringBufferSize)

Sets up the RX ring buffer.

This function sets up the RX ring buffer to a specific UART handle.

When the RX ring buffer is used, data received is stored into the ring buffer even when the user doesn't call the UART_TransferReceiveNonBlocking() API. If there is already data received in the ring buffer, the user can get the received data from the ring buffer directly.

Note: When using RX ring buffer, one byte is reserved for internal use. In other words, if ringBufferSize is 32, then only 31 bytes are used for saving data.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.
- ringBuffer – Start address of ring buffer for background receiving. Pass NULL to disable the ring buffer.
- ringBufferSize – size of the ring buffer.

void LPUART_TransferStopRingBuffer(LPUART_Type *base, *lpuart_handle_t* *handle)

Aborts the background transfer and uninstalls the ring buffer.

This function aborts the background transfer and uninstalls the ring buffer.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.

size_t LPUART_TransferGetRxRingBufferLength(LPUART_Type *base, *lpuart_handle_t* *handle)

Get the length of received data in RX ring buffer.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.

Returns

Length of received data in RX ring buffer.

void LPUART_TransferAbortSend(LPUART_Type *base, *lpuart_handle_t* *handle)

Aborts the interrupt-driven data transmit.

This function aborts the interrupt driven data sending. The user can get the remainBtyes to find out how many bytes are not sent out.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.

status_t LPUART_TransferGetSendCount(LPUART_Type *base, *lpuart_handle_t* *handle, uint32_t *count)

Gets the number of bytes that have been sent out to bus.

This function gets the number of bytes that have been sent out to bus by an interrupt method.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.
- count – Send bytes count.

Return values

- kStatus_NoTransferInProgress – No send in progress.
- kStatus_InvalidArgument – Parameter is invalid.
- kStatus_Success – Get successfully through the parameter count;

status_t LPUART_TransferReceiveNonBlocking(LPUART_Type *base, *lpuart_handle_t* *handle, *lpuart_transfer_t* *xfer, size_t *receivedBytes)

Receives a buffer of data using the interrupt method.

This function receives data using an interrupt method. This is a non-blocking function which returns without waiting to ensure that all data are received. If the RX ring buffer is used and not empty, the data in the ring buffer is copied and the parameter receivedBytes shows how many bytes are copied from the ring buffer. After copying, if the data in the ring buffer is not enough for read, the receive request is saved by the LPUART driver. When the new data arrives, the receive request is serviced first. When all data is received, the LPUART driver notifies the upper layer through a callback function and passes a status parameter kStatus_UART_RxIdle. For example, the upper layer needs 10 bytes but there are only 5 bytes in ring buffer. The 5 bytes are copied to xfer->data, which returns with the parameter receivedBytes set to 5. For the remaining 5 bytes, the newly arrived data is saved from xfer->data[5]. When 5 bytes are received, the LPUART driver notifies the upper layer. If the RX ring buffer is not enabled, this function enables the RX and RX interrupt to receive data to xfer->data. When all data is received, the upper layer is notified.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.
- xfer – LPUART transfer structure, see uart_transfer_t.
- receivedBytes – Bytes received from the ring buffer directly.

Return values

- kStatus_Success – Successfully queue the transfer into the transmit queue.
- kStatus_LPUART_RxBusy – Previous receive request is not finished.
- kStatus_InvalidArgument – Invalid argument.

void LPUART_TransferAbortReceive(LPUART_Type *base, *lpuart_handle_t* *handle)

Aborts the interrupt-driven data receiving.

This function aborts the interrupt-driven data receiving. The user can get the remainBytes to find out how many bytes not received yet.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.

status_t LPUART_TransferGetReceiveCount(LPUART_Type *base, *lpuart_handle_t* *handle, uint32_t *count)

Gets the number of bytes that have been received.

This function gets the number of bytes that have been received.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.
- count – Receive bytes count.

Return values

- kStatus_NoTransferInProgress – No receive in progress.
- kStatus_InvalidArgument – Parameter is invalid.
- kStatus_Success – Get successfully through the parameter count;

void LPUART_TransferHandleIRQ(LPUART_Type *base, void *irqHandle)

LPUART IRQ handle function.

This function handles the LPUART transmit and receive IRQ request.

Parameters

- base – LPUART peripheral base address.
- irqHandle – LPUART handle pointer.

void LPUART_TransferHandleErrorIRQ(LPUART_Type *base, void *irqHandle)

LPUART Error IRQ handle function.

This function handles the LPUART error IRQ request.

Parameters

- base – LPUART peripheral base address.
- irqHandle – LPUART handle pointer.

void LPUART_DriverIRQHandler(uint32_t instance)

LPUART driver IRQ handler common entry.

This function provides the common IRQ request entry for LPUART.

Parameters

- instance – LPUART instance.

FSL_LPUART_DRIVER_VERSION

LPUART driver version.

Error codes for the LPUART driver.

Values:

enumerator kStatus_LPUART_TxBusy

TX busy

enumerator kStatus_LPUART_RxBusy

RX busy

enumerator kStatus_LPUART_TxIdle
LPUART transmitter is idle.

enumerator kStatus_LPUART_RxIdle
LPUART receiver is idle.

enumerator kStatus_LPUART_TxWatermarkTooLarge
TX FIFO watermark too large

enumerator kStatus_LPUART_RxWatermarkTooLarge
RX FIFO watermark too large

enumerator kStatus_LPUART_FlagCannotClearManually
Some flag can't manually clear

enumerator kStatus_LPUART_Error
Error happens on LPUART.

enumerator kStatus_LPUART_RxRingBufferOverrun
LPUART RX software ring buffer overrun.

enumerator kStatus_LPUART_RxHardwareOverrun
LPUART RX receiver overrun.

enumerator kStatus_LPUART_NoiseError
LPUART noise error.

enumerator kStatus_LPUART_FramingError
LPUART framing error.

enumerator kStatus_LPUART_ParityError
LPUART parity error.

enumerator kStatus_LPUART_BaudrateNotSupport
Baudrate is not support in current clock source

enumerator kStatus_LPUART_IdleLineDetected
IDLE flag.

enumerator kStatus_LPUART_Timeout
LPUART times out.

enum _lpuart_parity_mode
LPUART parity mode.
Values:

enumerator kLPUART_ParityDisabled
Parity disabled

enumerator kLPUART_ParityEven
Parity enabled, type even, bit setting: PE|PT = 10

enumerator kLPUART_ParityOdd
Parity enabled, type odd, bit setting: PE|PT = 11

enum _lpuart_data_bits
LPUART data bits count.
Values:

enumerator kLPUART_EightDataBits
Eight data bit

enumerator kLPUART_SevenDataBits
Seven data bit

enum _lpuart_stop_bit_count
LPUART stop bit count.
Values:

enumerator kLPUART_OneStopBit
One stop bit

enumerator kLPUART_TwoStopBit
Two stop bits

enum _lpuart_transmit_cts_source
LPUART transmit CTS source.
Values:

enumerator kLPUART_CtsSourcePin
CTS resource is the LPUART_CTS pin.

enumerator kLPUART_CtsSourceMatchResult
CTS resource is the match result.

enum _lpuart_transmit_cts_config
LPUART transmit CTS configure.
Values:

enumerator kLPUART_CtsSampleAtStart
CTS input is sampled at the start of each character.

enumerator kLPUART_CtsSampleAtIdle
CTS input is sampled when the transmitter is idle

enum _lpuart_transmit_rts_polarity

LPUART transmitter RTS polarity.

Values:

enumerator kLPUART_RtsPolarityLow

Transmitter RTS is active low.

enumerator kLPUART_RtsPolarityHigh

Transmitter RTS is active high.

enum _lpuart_idle_type_select

LPUART idle flag type defines when the receiver starts counting.

Values:

enumerator kLPUART_IdleTypeStartBit

Start counting after a valid start bit.

enumerator kLPUART_IdleTypeStopBit

Start counting after a stop bit.

enum _lpuart_idle_config

LPUART idle detected configuration. This structure defines the number of idle characters that must be received before the IDLE flag is set.

Values:

enumerator kLPUART_IdleCharacter1

the number of idle characters.

enumerator kLPUART_IdleCharacter2

the number of idle characters.

enumerator kLPUART_IdleCharacter4

the number of idle characters.

enumerator kLPUART_IdleCharacter8

the number of idle characters.

enumerator kLPUART_IdleCharacter16

the number of idle characters.

enumerator kLPUART_IdleCharacter32

the number of idle characters.

enumerator kLPUART_IdleCharacter64

the number of idle characters.

enumerator kLPUART_IdleCharacter128

the number of idle characters.

enum _lpuart_interrupt_enable

LPUART interrupt configuration structure, default settings all disabled.

This structure contains the settings for all LPUART interrupt configurations.

Values:

enumerator kLPUART_LinBreakInterruptEnable
LIN break detect. bit 7

enumerator kLPUART_RxActiveEdgeInterruptEnable
Receive Active Edge. bit 6

enumerator kLPUART_TxDataRegEmptyInterruptEnable
Transmit data register empty. bit 23

enumerator kLPUART_TransmissionCompleteInterruptEnable
Transmission complete. bit 22

enumerator kLPUART_RxDataRegFullInterruptEnable
Receiver data register full. bit 21

enumerator kLPUART_IdleLineInterruptEnable
Idle line. bit 20

enumerator kLPUART_RxOverrunInterruptEnable
Receiver Overrun. bit 27

enumerator kLPUART_NoiseErrorInterruptEnable
Noise error flag. bit 26

enumerator kLPUART_FramingErrorInterruptEnable
Framing error flag. bit 25

enumerator kLPUART_ParityErrorInterruptEnable
Parity error flag. bit 24

enumerator kLPUART_Match1InterruptEnable
Parity error flag. bit 15

enumerator kLPUART_Match2InterruptEnable
Parity error flag. bit 14

enumerator kLPUART_TxFifoOverflowInterruptEnable
Transmit FIFO Overflow. bit 9

enumerator kLPUART_RxFifoUnderflowInterruptEnable
Receive FIFO Underflow. bit 8

enumerator kLPUART_AllInterruptEnable

enum _lpuart_flags

LPUART status flags.

This provides constants for the LPUART status flags for use in the LPUART functions.

Values:

enumerator kLPUART_TxDataRegEmptyFlag

Transmit data register empty flag, sets when transmit buffer is empty. bit 23

enumerator kLPUART_TransmissionCompleteFlag

Transmission complete flag, sets when transmission activity complete. bit 22

enumerator kLPUART_RxDataRegFullFlag

Receive data register full flag, sets when the receive data buffer is full. bit 21

enumerator kLPUART_IdleLineFlag

Idle line detect flag, sets when idle line detected. bit 20

enumerator kLPUART_RxOverrunFlag

Receive Overrun, sets when new data is received before data is read from receive register. bit 19

enumerator kLPUART_NoiseErrorFlag

Receive takes 3 samples of each received bit. If any of these samples differ, noise flag sets. bit 18

enumerator kLPUART_FramingErrorFlag

Frame error flag, sets if logic 0 was detected where stop bit expected. bit 17

enumerator kLPUART_ParityErrorFlag

If parity enabled, sets upon parity error detection. bit 16

enumerator kLPUART_LinBreakFlag

LIN break detect interrupt flag, sets when LIN break char detected and LIN circuit enabled. bit 31

enumerator kLPUART_RxActiveEdgeFlag

Receive pin active edge interrupt flag, sets when active edge detected. bit 30

enumerator kLPUART_RxActiveFlag

Receiver Active Flag (RAF), sets at beginning of valid start. bit 24

enumerator kLPUART_DataMatch1Flag

The next character to be read from LPUART_DATA matches MA1. bit 15

enumerator kLPUART_DataMatch2Flag

The next character to be read from LPUART_DATA matches MA2. bit 14

enumerator kLPUART_TxFifoEmptyFlag

TXEMPT bit, sets if transmit buffer is empty. bit 7

enumerator kLPUART_RxFifoEmptyFlag
RXEMPT bit, sets if receive buffer is empty. bit 6

enumerator kLPUART_TxFifoOverflowFlag
TXOF bit, sets if transmit buffer overflow occurred. bit 1

enumerator kLPUART_RxFifoUnderflowFlag
RXUF bit, sets if receive buffer underflow occurred. bit 0

enumerator kLPUART_AllClearFlags

enumerator kLPUART_AllFlags

typedef enum *_lpuart_parity_mode* lpuart_parity_mode_t
LPUART parity mode.

typedef enum *_lpuart_data_bits* lpuart_data_bits_t
LPUART data bits count.

typedef enum *_lpuart_stop_bit_count* lpuart_stop_bit_count_t
LPUART stop bit count.

typedef enum *_lpuart_transmit_cts_source* lpuart_transmit_cts_source_t
LPUART transmit CTS source.

typedef enum *_lpuart_transmit_cts_config* lpuart_transmit_cts_config_t
LPUART transmit CTS configure.

typedef enum *_lpuart_transmit_rts_polarity* lpuart_transmit_rts_polarity_t
LPUART transmitter RTS polarity.

typedef enum *_lpuart_idle_type_select* lpuart_idle_type_select_t
LPUART idle flag type defines when the receiver starts counting.

typedef enum *_lpuart_idle_config* lpuart_idle_config_t
LPUART idle detected configuration. This structure defines the number of idle characters that must be received before the IDLE flag is set.

typedef struct *_lpuart_config* lpuart_config_t
LPUART configuration structure.

typedef struct *_lpuart_transfer* lpuart_transfer_t
LPUART transfer structure.

typedef struct *_lpuart_handle* lpuart_handle_t

typedef void (*lpuart_transfer_callback_t)(LPUART_Type *base, *lpuart_handle_t* *handle, *status_t* status, void *userData)
LPUART transfer callback function.

typedef void (*lpuart_isr_t)(LPUART_Type *base, void *handle)

void *s_lpuartHandle[]

const IRQn_Type s_lpuartTxIRQ[]

lpuart_isr_t s_lpuartIsr[]

UART_RETRY_TIMES
Retry times for waiting flag.

struct _lpuart_config
#include <fsl_lpuart.h> LPUART configuration structure.

Public Members

uint32_t baudRate_Bps
LPUART baud rate

lpuart_parity_mode_t parityMode
Parity mode, disabled (default), even, odd

lpuart_data_bits_t dataBitsCount
Data bits count, eight (default), seven

bool isMsb
Data bits order, LSB (default), MSB

lpuart_stop_bit_count_t stopBitCount
Number of stop bits, 1 stop bit (default) or 2 stop bits

uint8_t txFifoWatermark
TX FIFO watermark

uint8_t rxFifoWatermark
RX FIFO watermark

bool enableRxRTS
RX RTS enable

bool enableTxRTS
TX RTS enable

bool enableTxCTS
TX CTS enable

lpuart_transmit_cts_source_t txCtsSource
: TX CTS source

lpuart_transmit_cts_config_t txCtsConfig
: TX CTS configure

lpuart_transmit_rts_polarity_t txRtsPolarity
: TX RTS polarity

uint8_t rtsWatermark
: RTS watermark

lpuart_idle_type_select_t rxIdleType
: RX IDLE type.

lpuart_idle_config_t rxIdleConfig
: RX IDLE configuration.

bool enableTx
: Enable TX

bool enableRx
: Enable RX

bool swapTxdRxd
: Swap TXD and RXD pins

bool inverseTxd
: Transmit Data Inversion - Setting true reverses the polarity of the transmitted data output

struct __lpuart__transfer
: *#include <fsl_lpuart.h>* LPUART transfer structure.

Public Members

size_t dataSize
: The byte count to be transfer.

struct __lpuart__handle
: *#include <fsl_lpuart.h>* LPUART handle structure.

Public Members

volatile size_t txDataSize
: Size of the remaining data to send.

size_t txDataSizeAll
: Size of the data to send out.

volatile size_t rxDataSize
: Size of the remaining data to receive.

size_t rxDataSizeAll
: Size of the data to receive.

size_t rxRingBufferSize
: Size of the ring buffer.

volatile uint16_t rxRingBufferHead
: Index for the driver to store received data into ring buffer.

volatile uint16_t rxRingBufferTail
: Index for the user to get data from the ring buffer.

lpuart_transfer_callback_t callback
: Callback function.

void *userData
: LPUART callback function parameter.

volatile uint8_t txState
: TX transfer state.

volatile uint8_t rxState
: RX transfer state.

bool isSevenDataBits
: Seven data bits flag.

bool is16bitData
: 16bit data bits flag, only used for 9bit or 10bit data

union ___unnamed67___

Public Members

uint8_t *data
: The buffer of data to be transfer.

uint8_t *rxData
: The buffer to receive data.

uint16_t *rxData16
: The buffer to receive data.

const uint8_t *txData
The buffer of data to be sent.

const uint16_t *txData16
The buffer of data to be sent.

union ___unnamed69___

Public Members

const uint8_t *volatile txData
Address of remaining data to send.

const uint16_t *volatile txData16
Address of remaining data to send.

union ___unnamed71___

Public Members

uint8_t *volatile rxData
Address of remaining data to receive.

uint16_t *volatile rxData16
Address of remaining data to receive.

union ___unnamed73___

Public Members

uint8_t *rxRingBuffer
Start address of the receiver ring buffer.

uint16_t *rxRingBuffer16
Start address of the receiver ring buffer.

2.59 LPUART eDMA Driver

void LPUART_TransferCreateHandleEDMA(LPUART_Type *base, *lpuart_edma_handle_t* *handle, *lpuart_edma_transfer_callback_t* callback, void *userData, *edma_handle_t* *txEdmaHandle, *edma_handle_t* *rxEdmaHandle)

Initializes the LPUART handle which is used in transactional functions.

Note: This function disables all LPUART interrupts.

Parameters

- base – LPUART peripheral base address.
- handle – Pointer to lpuart_edma_handle_t structure.
- callback – Callback function.
- userData – User data.
- txEdmaHandle – User requested DMA handle for TX DMA transfer.
- rxEdmaHandle – User requested DMA handle for RX DMA transfer.

status_t LPUART_SendEDMA(LPUART_Type *base, *lpuart_edma_handle_t* *handle, *lpuart_transfer_t* *xfer)

Sends data using eDMA.

This function sends data using eDMA. This is a non-blocking function, which returns right away. When all data is sent, the send callback function is called.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.
- xfer – LPUART eDMA transfer structure. See *lpuart_transfer_t*.

Return values

- kStatus_Success – if succeed, others failed.
- kStatus_LPUART_TxBusy – Previous transfer on going.
- kStatus_InvalidArgument – Invalid argument.

status_t LPUART_ReceiveEDMA(LPUART_Type *base, *lpuart_edma_handle_t* *handle, *lpuart_transfer_t* *xfer)

Receives data using eDMA.

This function receives data using eDMA. This is non-blocking function, which returns right away. When all data is received, the receive callback function is called.

Parameters

- base – LPUART peripheral base address.
- handle – Pointer to lpuart_edma_handle_t structure.
- xfer – LPUART eDMA transfer structure, see *lpuart_transfer_t*.

Return values

- kStatus_Success – if succeed, others fail.
- kStatus_LPUART_RxBusy – Previous transfer ongoing.
- kStatus_InvalidArgument – Invalid argument.

void LPUART_TransferAbortSendEDMA(LPUART_Type *base, *lpuart_edma_handle_t* *handle)

Aborts the sent data using eDMA.

This function aborts the sent data using eDMA.

Parameters

- base – LPUART peripheral base address.
- handle – Pointer to lpuart_edma_handle_t structure.

void LPUART_TransferAbortReceiveEDMA(LPUART_Type *base, *lpuart_edma_handle_t* *handle)

Aborts the received data using eDMA.

This function aborts the received data using eDMA.

Parameters

- base – LPUART peripheral base address.
- handle – Pointer to lpuart_edma_handle_t structure.

status_t LPUART_TransferGetSendCountEDMA(LPUART_Type *base, *lpuart_edma_handle_t* *handle, uint32_t *count)

Gets the number of bytes written to the LPUART TX register.

This function gets the number of bytes written to the LPUART TX register by DMA.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.
- count – Send bytes count.

Return values

- kStatus_NoTransferInProgress – No send in progress.
- kStatus_InvalidArgument – Parameter is invalid.
- kStatus_Success – Get successfully through the parameter count;

status_t LPUART_TransferGetReceiveCountEDMA(LPUART_Type *base, *lpuart_edma_handle_t* *handle, uint32_t *count)

Gets the number of received bytes.

This function gets the number of received bytes.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.
- count – Receive bytes count.

Return values

- kStatus_NoTransferInProgress – No receive in progress.
- kStatus_InvalidArgument – Parameter is invalid.
- kStatus_Success – Get successfully through the parameter count;

void LPUART_TransferEdmaHandleIRQ(LPUART_Type *base, void *lpuartEdmaHandle)

LPUART eDMA IRQ handle function.

This function handles the LPUART tx complete IRQ request and invoke user callback. It is not set to static so that it can be used in user application.

Note: This function is used as default IRQ handler by double weak mechanism. If user's specific IRQ handler is implemented, make sure this function is invoked in the handler.

Parameters

- base – LPUART peripheral base address.
- lpuartEdmaHandle – LPUART handle pointer.

FSL_LPUART_EDMA_DRIVER_VERSION

LPUART EDMA driver version.

typedef struct *_lpuart_edma_handle* lpuart_edma_handle_t

typedef void (*lpuart_edma_transfer_callback_t)(LPUART_Type *base, *lpuart_edma_handle_t* *handle, *status_t* status, void *userData)

LPUART transfer callback function.

struct _lpuart_edma_handle

#include <fsl_lpuart_edma.h> LPUART eDMA handle.

Public Members

lpuart_edma_transfer_callback_t callback

Callback function.

void *userData

LPUART callback function parameter.

size_t rxDataSizeAll

Size of the data to receive.

size_t txDataSizeAll

Size of the data to send out.

edma_handle_t *txEdmaHandle

The eDMA TX channel used.

edma_handle_t *rxEdmaHandle

The eDMA RX channel used.

uint8_t nbytes

eDMA minor byte transfer count initially configured.

volatile uint8_t txState

TX transfer state.

volatile uint8_t rxState

RX transfer state

2.60 MAU: Math Accelerator Unit Driver

typedef int16_t mau_q15_t
MAU Q15 type.

typedef int32_t mau_q31_t
MAU Q31 type.

mau_result_t res {return (base->RES_STATUS >> (8 << (uint8_t)(res))) & 0xFF

mau_result_t uint32_t mask {base->RES_STATUS &= ~((mask & 0xFF) << (8 << (uint8_t)(res)))

uint32_t input

(*volatile uint32_t)(addr))) = input

(*volatile float)(addr))) = input

float float *pSin = (*((volatile float*)((uint32_t)(&MAU0->RES0) + (sin_res « 2))))

float float float *pCos = (*((volatile float*)((uint32_t)(&MAU0->RES0) + (cos_res « 2))))

float float float mau_result_t sin_res

float float float mau_result_t mau_result_t cos_res = { uint32_t sin_addr = (((uint32_t)base) | ((kMAU_DT_FL

uint32_t cos_addr = (((uint32_t)base) | ((*kMAU_DT_FLOAT*) « 9U) | ((cos_res) « 7U) |
((*kMAU_MOPC_COS*) « 2U))

float input_value = *input*

static inline static __attribute__ ((al-
ways_inline)) void MAU_GetDefaultConfig(mau_config_t *config)
Gets the default configuration structure.

Calculate the arctangent(X)/PI for Q15.

Calculate the sine(PI*X) and cosine(PI*X) for Q15.

Calculate the cosine(PI*X) for Q15.

Calculate the sine(PI*X) for Q15.

Calculate the reciprocal square root for Q15.

Calculate the square root for Q15.

Calculate the reciprocal for Q15.

Calculate the arctangent(X)/PI for Q31.

Calculate the sine(PI*X) and cosine(PI*X) for Q31.

Calculate the cosine(PI*X) for Q31.

Calculate the sine(PI*X) for Q31.

Calculate the reciprocal square root for Q31.

Calculate the square root for Q31.

Calculate the reciprocal for Q31.

Calculate the arctangent(X)/PI for float.

Calculate the sine(PI*X) and cosine(PI*X) for float.

Calculate the cosine(PI*X) for float.

Calculate the sine(PI*X) for float.

Calculate the reciprocal square root for float.

Calculate the square root for float.

Calculate the reciprocal for float.

Calculate the square root for uint32.

Clears the result register status flag.

Gets the result register status flag.

This function initializes the MAU configuration structure to a default value.

Parameters

- base – MAU peripheral base address.
- res – MAU result register. see *mau_result_t*.
- base – MAU peripheral base address.
- res – MAU result register. see *mau_result_t*.
- mask – MAU result register flag mask, see *mau_flags_t*.
- base – MAU peripheral base address.
- input – Input data.
- res – MAU result register. see *mau_result_t*.
- base – MAU peripheral base address.
- input – Input data.
- res – MAU result register. see *mau_result_t*.
- base – MAU peripheral base address.
- input – Input data.
- pSin – Points to the block of sine output data
- pCos – Points to the block of cosine output data
- sin_res – MAU result register for sine. see *mau_result_t*.
- cos_res – MAU result register for cosine. see *mau_result_t*.
- base – MAU peripheral base address.
- input – Input data.
- res – MAU result register. see *mau_result_t*.
- base – MAU peripheral base address.
- input – Input data.
- res – MAU result register. see *mau_result_t*.

Returns
uint32_t MAU result register flags, see *mau_flags_t*.

Returns
uint32_t

Returns
float

Returns
mau_q31_t

Returns
mau_q15_t

void MAU_Init(MAU_Type *base, *mau_config_t* *config)

Initializes MAU instance with the user configuration structure.

Parameters

- base – MAU peripheral base address.
- config – Pointer to a user-defined configuration structure.

void MAU_Deinit(MAU_Type *base)

Deinitializes MAU instance.

Parameters

- base – MAU peripheral base address.

FSL_MAU_DRIVER_VERSION

MAU driver version.

enum _mau_data_type

MAU data type.

Values:

enumerator kMAU_DT_UINT

enumerator kMAU_DT_INT

enumerator kMAU_DT_Q1X

enumerator kMAU_DT_FLOAT

enum _mau_result

MAU result register.

Values:

enumerator kMAU_RES0

enumerator kMAU_RES1

enumerator kMAU_RES2

enumerator kMAU_RES3

enum _mau_mopc

MAU calculation code.

Values:

enumerator kMAU_MOPC_BYPASS

enumerator kMAU_MOPC_RECIP

enumerator kMAU_MOPC_SQRT

enumerator kMAU_MOPC_SQRT_RECIP

enumerator kMAU_MOPC_COS

enumerator kMAU_MOPC_SIN

enumerator kMAU_MOPC_ATAN

enum _mau_flags

MAU result register status flag.

Values:

enumerator kMAU_FLAG_NX

enumerator kMAU_FLAG_UF

enumerator kMAU_FLAG_OF

enumerator kMAU_FLAG_DZ

enumerator kMAU_FLAG_NV

enumerator kMAU_FLAG_ERR

enumerator kMAU_FLAG_OVWR

enumerator kMAU_FLAG_FULL

typedef enum *_mau_data_type* mau_data_type_t

MAU data type.

typedef enum *_mau_result* mau_result_t

MAU result register.

typedef enum *_mau_mopc* mau_mopc_t
MAU calculation code.

typedef enum *_mau_flags* mau_flags_t
MAU result register status flag.

typedef struct *_mau_config* mau_config_t
MAU configuration structure.

MAU_MATH_PI

MAU_DT_SET(dt)

MAU_RES_SET(res)

MAU_MOPC_SET(mopc)

MAU_INDIRECT_ADDR(base, dt, ds, mopc)

MAU_REG_UINT32(addr)

MAU_REG_Q15(addr)

MAU_REG_Q31(addr)

MAU_REG_FLOAT(addr)

CONFIG_MAU_ENABLE_CMSIS_DSP_API
Enable the MAU CMSIS DSP function.

CONFIG_MAU_ENABLE_CMSIS_DSP_ARM_SQRT_F32_API
Enable the MAU arm_sqrt_f32 function.

struct _mau_config
#include <fsl_mau.h> MAU configuration structure.

Public Members

bool enableRes0Interrupt
Enable RES0 interrupt.

bool enableRes1Interrupt
Enable RES1 interrupt.

bool enableRes2Interrupt
Enable RES2 interrupt.

bool enableRes3Interrupt
Enable RES3 interrupt.

2.61 MCX_CMC: Core Mode Controller Driver

enum _cmc_power_mode_protection

CMC power mode Protection enumeration.

Values:

enumerator kCMC_AllowDeepSleepMode

Allow Deep Sleep mode.

enumerator kCMC_AllowPowerDownMode

Allow Power Down mode.

enumerator kCMC_AllowDeepPowerDownMode

Allow Deep Power Down mode.

enumerator kCMC_AllowAllLowPowerModes

Allow Deep Sleep, Power Down, Deep Power Down modes.

enum _cmc_wakeup_sources

Wake up sources from the previous low power mode entry.

Note: *kCMC_WakeupFromUsbFs*, *kCMC_WakeupFromITRC*, *kCMC_WakeupFromCpu1* are not supported in MCXA family.

Values:

enumerator kCMC_WakeupFromResetInterruptOrPowerDown

Wakeup source is reset interrupt, or wake up from Deep Power Down.

enumerator kCMC_WakeupFromDebugReuqest

Wakeup source is debug request.

enumerator kCMC_WakeupFromInterrupt

Wakeup source is interrupt.

enumerator kCMC_WakeupFromDMAWakeup

Wakeup source is DMA Wakeup.

enumerator kCMC_WakeupFromWUURequest

Wakeup source is WUU request.

enumerator kCMC_WakeupFromUsbFs

Wakeup source is USBFS(USB0).

enumerator kCMC_WakeupFromITRC

Wakeup source is ITRC.

enumerator kCMC_WakeupFromCpu1
Wakeup source is CPU1.

enum _cmc_system_reset_interrupt_enable
System Reset Interrupt enable enumeration.
Values:

enumerator kCMC_PinResetInterruptEnable
Pin Reset interrupt enable.

enumerator kCMC_DAPResetInterruptEnable
DAP Reset interrupt enable.

enumerator kCMC_LowPowerAcknowledgeTimeoutResetInterruptEnable
Low Power Acknowledge Timeout Reset interrupt enable.

enumerator kCMC_SoftwareResetInterruptEnable
Software Reset interrupt enable.

enumerator kCMC_LockupResetInterruptEnable
Lockup Reset interrupt enable.

enum _cmc_system_reset_interrupt_flag
CMC System Reset Interrupt Status flag.
Values:

enumerator kCMC_PinResetInterruptFlag
Pin Reset interrupt flag.

enumerator kCMC_DAPResetInterruptFlag
DAP Reset interrupt flag.

enumerator kCMC_LowPowerAcknowledgeTimeoutResetFlag
Low Power Acknowledge Timeout Reset interrupt flag.

enumerator kCMC_SoftwareResetInterruptFlag
Software Reset interrupt flag.

enumerator kCMC_LockupResetInterruptFlag
Lock up Reset interrupt flag.

enum _cmc_system_sram_arrays
CMC System SRAM arrays low power mode enable enumeration.
Values:

enumerator kCMC_RAMX0
Used to control RAMX0.

enumerator kCMC_RAMX1
Used to control RAMX1.

enumerator kCMC_RAMX2
Used to control RAMX2.

enumerator kCMC_RAMB
Used to control RAMB.

enumerator kCMC_RAMC0
Used to control RAMC0.

enumerator kCMC_RAMC1
Used to control RAMC1.

enumerator kCMC_RAMD0
Used to control RAMD0.

enumerator kCMC_RAMD1
Used to control RAMD1.

enumerator kCMC_RAME0
Used to control RAME0.

enumerator kCMC_RAME1
Used to control RAME1.

enumerator kCMC_RAMF0
Used to control RAMF0.

enumerator kCMC_RAMF1
Used to control RAMF1.

enumerator kCMC_RAMG0_RAMG1
Used to control RAMG0 and RAMG1.

enumerator kCMC_RAMG2_RAMG3
Used to control RAMG2 and RAMG3.

enumerator kCMC_RAMH0_RAMH1
Used to control RAMH0 and RAMH1.

enumerator kCMC_LPCAC
Used to control LPCAC.

enumerator kCMC_DMA0_DMA1_PKC
Used to control DMA0, DMA1 and PKC.

enumerator kCMC_USB0
Used to control USB0.

enumerator kCMC_PQ
Used to control PQ.

enumerator kCMC_CAN0_CAN1_ENET_USB1
Used to control CAN0, CAN1, ENET, USB1.

enumerator kCMC_FlexSPI
Used to control FlexSPI.

enumerator kCMC_AllSramArrays
Mask of all System SRAM arrays.

enum _cmc_system_reset_sources
System reset sources enumeration.
Values:

enumerator kCMC_WakeUpReset
The reset caused by a wakeup from Power Down or Deep Power Down mode.

enumerator kCMC_PORReset
The reset caused by power on reset detection logic.

enumerator kCMC_WarmReset
The last reset source is a warm reset source.

enumerator kCMC_FatalReset
The last reset source is a fatal reset source.

enumerator kCMC_PinReset
The reset caused by the RESET_b pin.

enumerator kCMC_DAPReset
The reset caused by a reset request from the Debug Access port.

enumerator kCMC_ResetTimeout
The reset caused by a timeout or other error condition in the system reset generation.

enumerator kCMC_LowPowerAcknowledgeTimeoutReset
The reset caused by a timeout in low power mode entry logic.

enumerator kCMC_SCGReset
The reset caused by a loss of clock or loss of lock event in the SCG.

enumerator kCMC_SoftwareReset
The reset caused by a software reset request.

enumerator kCMC_LockUoReset
The reset caused by the ARM core indication of a LOCKUP event.

enumerator kCMC_JTAGSystemReset
The reset caused by a JTAG system reset request.

enum _cmc_core_clock_gate_status
Indicate the core clock was gated.
Values:

enumerator kCMC_CoreClockNotGated
Core clock not gated.

enumerator kCMC_CoreClockGated
Core clock was gated due to low power mode entry.

enum _cmc_clock_mode
CMC clock mode enumeration.
Values:

enumerator kCMC_GateNoneClock
No clock gating.

enumerator kCMC_GateCoreClock
Gate Core clock.

enumerator kCMC_GateCorePlatformClock
Gate Core clock and platform clock.

enumerator kCMC_GateAllSystemClocks
Gate all System clocks, without getting core entering into low power mode.

enumerator kCMC_GateAllSystemClocksEnterLowPowerMode
Gate all System clocks, with core entering into low power mode.

enum _cmc_low_power_mode
CMC power mode enumeration.
Values:

enumerator kCMC_ActiveOrSleepMode
Select Active/Sleep mode.

enumerator kCMC_DeepSleepMode
Select Deep Sleep mode when a core executes WFI or WFE instruction.

enumerator kCMC_PowerDownMode
Select Power Down mode when a core executes WFI or WFE instruction.

enumerator kCMC_DeepPowerDown

Select Deep Power Down mode when a core executes WFI or WFE instruction.

typedef enum *_cmc_core_clock_gate_status* cmc_core_clock_gate_status_t

Indicate the core clock was gated.

typedef enum *_cmc_clock_mode* cmc_clock_mode_t

CMC clock mode enumeration.

typedef enum *_cmc_low_power_mode* cmc_low_power_mode_t

CMC power mode enumeration.

typedef struct *_cmc_reset_pin_config* cmc_reset_pin_config_t

CMC reset pin configuration.

typedef struct *_cmc_power_domain_config* cmc_power_domain_config_t

power mode configuration for each power domain.

FSL_CMC_DRIVER_VERSION

CMC driver version 2.5.0.

CMC_BLR_LOCK_FIELD_WIDTH

CMC_BLR_LOCK_IDX_MASK(index)

CMC_BLR_LOCK_IDX_SHIFT(index)

CMC_BLR_LOCK_IDX(index, value)

void CMC_SetClockMode(CMC_Type *base, *cmc_clock_mode_t* mode)

Sets clock mode.

This function configs the amount of clock gating when the core asserts Sleeping due to WFI, WFE or SLEEPONEXIT.

Parameters

- base – CMC peripheral base address.
- mode – System clock mode.

static inline void CMC_LockClockModeSetting(CMC_Type *base)

Locks the clock mode setting.

After invoking this function, any clock mode setting will be blocked.

Parameters

- base – CMC peripheral base address.

static inline *cmc_core_clock_gate_status_t* CMC_GetCoreClockGatedStatus(CMC_Type *base)

Gets the core clock gated status.

This function get the status to indicate whether the core clock is gated. The core clock gated status can be cleared by software.

Parameters

- base – CMC peripheral base address.

Returns
The status to indicate whether the core clock is gated.

static inline void CMC_ClearCoreClockGatedStatus(CMC_Type *base)

Clears the core clock gated status.

This function clear clock status flag by software.

Parameters

- base – CMC peripheral base address.

static inline uint8_t CMC_GetWakeupSource(CMC_Type *base)

Gets the Wakeup Source.

This function gets the Wakeup sources from the previous low power mode entry.

Parameters

- base – CMC peripheral base address.

Returns
The Wakeup sources from the previous low power mode entry. See *_cmc_wakeup_sources* for details.

static inline *cmc_clock_mode_t* CMC_GetClockMode(CMC_Type *base)

Gets the Clock mode.

This function gets the clock mode of the previous low power mode entry.

Parameters

- base – CMC peripheral base address.

Returns
The Low Power status.

static inline uint32_t CMC_GetSystemResetStatus(CMC_Type *base)

Gets the System reset status.

This function returns the system reset status. Those status updates on every MAIN Warm Reset to indicate the type/source of the most recent reset.

Parameters

- base – CMC peripheral base address.

Returns
The most recent system reset status. See *_cmc_system_reset_sources* for details.

static inline uint32_t CMC_GetStickySystemResetStatus(CMC_Type *base)

Gets the sticky system reset status since the last WAKE Cold Reset.

This function gets all source of system reset that have generated a system reset since the last WAKE Cold Reset, and that have not been cleared by software.

Parameters

- base – CMC peripheral base address.

Returns
System reset status that have not been cleared by software. See *_cmc_system_reset_sources* for details.

static inline void CMC_ClearStickySystemResetStatus(CMC_Type *base, uint32_t mask)

Clears the sticky system reset status flags.

Parameters

- base – CMC peripheral base address.
- mask – Bitmap of the sticky system reset status to be cleared.

static inline uint8_t CMC_GetResetCount(CMC_Type *base)

Gets the number of reset sequences completed since the last Cold Reset.

Parameters

- base – CMC peripheral base address.

Returns

The number of reset sequences.

void CMC_SetPowerModeProtection(CMC_Type *base, uint32_t allowedModes)

Configures all power mode protection settings.

This function configures the power mode protection settings for supported power modes. This should be done before set the lowPower mode for each power doamin.

The allowed lowpower modes are passed as bit map. For example, to allow Sleep and DeepSleep, use CMC_SetPowerModeProtection(CMC_base, kCMC_AllowSleepMode|kCMC_AllowDeepSleepMode). To allow all low power modes, use CMC_SetPowerModeProtection(CMC_base, kCMC_AllowAllLowPowerModes).

Parameters

- base – CMC peripheral base address.
- allowedModes – Bitmaps of the allowed power modes. See *_cmc_power_mode_protection* for details.

static inline void CMC_LockPowerModeProtectionSetting(CMC_Type *base)

Locks the power mode protection.

This function locks the power mode protection. After invoking this function, any power mode protection setting will be ignored.

Parameters

- base – CMC peripheral base address.

static inline void CMC_SetGlobalPowerMode(CMC_Type *base, *cmc_low_power_mode_t* lowPowerMode)

Config the same lowPower mode for all power domain.

This function configures the same low power mode for MAIN power domian and WAKE power domain.

Parameters

- base – CMC peripheral base address.
- lowPowerMode – The desired lowPower mode. See *cmc_low_power_mode_t* for details.

static inline void CMC_SetMAINPowerMode(CMC_Type *base, *cmc_low_power_mode_t* lowPowerMode)

Configures entry into low power mode for the MAIN Power domain.

This function configures the low power mode for the MAIN power domian, when the core executes WFI/WFE instruction. The available lowPower modes are defined in the *cmc_low_power_mode_t*.

Parameters

- base – CMC peripheral base address.

- lowPowerMode – The desired lowPower mode. See *cmc_low_power_mode_t* for details.

static inline *cmc_low_power_mode_t* CMC_GetMAINPowerMode(CMC_Type *base)

Gets the power mode of the MAIN Power domain.

Parameters

- base – CMC peripheral base address.

Returns

The power mode of MAIN Power domain. See *cmc_low_power_mode_t* for details.

void CMC_ConfigResetPin(CMC_Type *base, const *cmc_reset_pin_config_t* *config)

Configure reset pin.

This function configures reset pin. When enabled, the low power filter is enabled in both Active and Low power modes, the reset filter is only enabled in Active mode. When both filers are enabled, they operate in series.

Parameters

- base – CMC peripheral base address.
- config – Pointer to the reset pin config structure.

static inline void CMC_EnableSystemResetInterrupt(CMC_Type *base, uint32_t mask)

Enable system reset interrupts.

This function enables the system reset interrupts. The assertion of non-fatal warm reset can be delayed for 258 cycles of the 32K_CLK clock while an enabled interrupt is generated. Then Software can perform a graceful shutdown or abort the non-fatal warm reset provided the pending reset source is cleared by resetting the reset source and then clearing the pending flag.

Parameters

- base – CMC peripheral base address.
- mask – System reset interrupts. See *_cmc_system_reset_interrupt_enable* for details.

static inline void CMC_DisableSystemResetInterrupt(CMC_Type *base, uint32_t mask)

Disable system reset interrupts.

This function disables the system reset interrupts.

Parameters

- base – CMC peripheral base address.
- mask – System reset interrupts. See *_cmc_system_reset_interrupt_enable* for details.

static inline uint32_t CMC_GetSystemResetInterruptFlags(CMC_Type *base)

Gets System Reset interrupt flags.

This function returns the System reset interrupt flags.

Parameters

- base – CMC peripheral base address.

Returns

System reset interrupt flags. See *_cmc_system_reset_interrupt_flag* for details.

static inline void CMC_ClearSystemResetInterruptFlags(CMC_Type *base, uint32_t mask)

Clears System Reset interrupt flags.

This function clears system reset interrupt flags. The pending reset source can be cleared by resetting the source of the reset and then clearing the pending flags.

Parameters

- base – CMC peripheral base address.
- mask – System Reset interrupt flags. See *_cmc_system_reset_interrupt_flag* for details.

static inline void CMC_EnableNonMaskablePinInterrupt(CMC_Type *base, bool enable)

Enable/Disable Non maskable Pin interrupt.

Parameters

- base – CMC peripheral base address.
- enable – Enable or disable Non maskable pin interrupt. true - enable Non-maskable pin interrupt. false - disable Non-maskable pin interupt.

static inline uint8_t CMC_GetISPMODEPinLogic(CMC_Type *base)

Gets the logic state of the ISPMODE_n pin.

This function returns the logic state of the ISPMODE_n pin on the last negation of RESET_b pin.

Parameters

- base – CMC peripheral base address.

Returns

The logic state of the ISPMODE_n pin on the last negation of RESET_b pin.

static inline void CMC_ClearISPMODEPinLogic(CMC_Type *base)

Clears ISPMODE_n pin state.

Parameters

- base – CMC peripheral base address.

static inline void CMC_ForceBootConfiguration(CMC_Type *base, bool assert)

Set the logic state of the BOOT_CONFIGn pin.

This function force the logic state of the Boot_Confign pin to assert on next system reset.

Parameters

- base – CMC peripheral base address.
- assert – Assert the corresponding pin or not. true - Assert corresponding pin on next system reset. false - No effect.

static inline uint32_t CMC_GetBootRomStatus(CMC_Type *base)

Gets the status information written by the BootROM.

Parameters

- base – CMC peripheral base address.

Returns

The status information written by the BootROM.

static inline void CMC_SetBootRomStatus(CMC_Type *base, uint32_t statValue)

Sets the bootROM status value.

Note: This function is useful when result of CMC_CheckBootRomRegisterWrittable() is true.

Parameters

- base – CMC peripheral base address.
- stat – The state value to set.

static inline uint32_t CMC_GetBootRomStatus(CMC_Type *base, uint8_t index)

Gets the information written by the BootROM.

Parameters

- base – CMC peripheral base address.
- index – The index of BootROM status register, ranges from 0.

Returns

The status information written by the BootROM.

static inline void CMC_WriteBootRomStatusReg(CMC_Type *base, uint8_t index, uint32_t value)

Writes value to BootROM status register, in this way, BootROM status registers are used as general purpose register.

Note: Value in BootROM status registers are reset in cold reset.

Parameters

- base – CMC peripheral base address.
- index – The index of BootROM status register, ranges from 0.
- value – Value to write.

static inline void CMC_LockWriteOperationToBootRomStatusReg(CMC_Type *base, uint8_t index)

Lock write operation to BootROM status register and BootROM Lock register.

Note: If locked, BootROM status register cannot be written.

Note: Once locked, only cold reset can reset related register.

Parameters

- base – CMC peripheral base address.
- index – The index of BootROM status register, ranges from 0.

static inline bool CMC_CheckBootRomStatusRegWriteLocked(CMC_Type *base, uint8_t index)

Check if BootROM status register can be written.

Parameters

- base – CMC peripheral base address.

- index – The index of BootROM status register, ranges from 0.

Return values

- true – The selected BootRom status register is locked and cannot be written.
- false – The selected BootRom Status register is unlocked and cannot be written.

void CMC_PowerOffSRAMAllMode(CMC_Type *base, uint32_t mask)

Power off the selected system SRAM always.

Note: This function power off the selected system SRAM always. The SRAM arrays should not be accessed while they are shut down. SRAM array contents are not retained if they are powered off.

Note: Once invoked, the previous settings will be overwritten.

Parameters

- base – CMC peripheral base address.
- mask – Bitmap of the SRAM arrays to be powered off all modes. See *_cmc_system_sram_arrays* for details. Check Reference Manual for the SRAM region and mask bit relationship.

static inline void CMC_PowerOnSRAMAllMode(CMC_Type *base, uint32_t mask)

Power on SRAM during all mode.

Note: Once invoked, the previous settings will be overwritten.

Parameters

- base – CMC peripheral base address.
- mask – Bitmap of the SRAM arrays to be powered on all modes. See *_cmc_system_sram_arrays* for details. Check Reference Manual for the SRAM region and mask bit relationship.

void CMC_PowerOffSRAMLowPowerOnly(CMC_Type *base, uint32_t mask)

Power off the selected system SRAM during low power modes only.

This function power off the selected system SRAM only during low power mode. SRAM array contents are not retained if they are power off.

Parameters

- base – CMC peripheral base address.
- mask – Bitmap of the SRAM arrays to be power off during low power mode only. See *_cmc_system_sram_arrays* for details. Check Reference Manual for the SRAM region and mask bit relationship.

static inline void CMC_PowerOnSRAMLowPowerOnly(CMC_Type *base, uint32_t mask)

Power on the selected system SRAM during low power modes only.

This function power on the selected system SRAM. The SRAM arrray contents are retained in low power modes.

Parameters

- base – CMC peripheral base address.
- mask – Bitmap of the SRAM arrays to be power on during low power mode only. See *_cmc_system_sram_arrays* for details. Check Reference Manual for the SRAM region and mask bit relationship.

void CMC_ConfigFlashMode(CMC_Type *base, bool doze, bool disable)

Configs the low power mode of the on-chip flash memory.

This function configs the low power mode of the on-chip flash memory.

Parameters

- base – CMC peripheral base address.
- doze – true: Flash is disabled while core is sleeping false: No effect.
- disable – true: Flash memory is placed in low power state. false: No effect.

static inline void CMC_EnableDebugOperation(CMC_Type *base, bool enable)

Enables/Disables debug Operation when the core sleep.

This function configs what happens to debug when core sleeps.

Parameters

- base – CMC peripheral base address.
- enable – Enable or disable Debug when Core is sleeping. true - Debug remains enabled when the core is sleeping. false - Debug is disabled when the core is sleeping.

void CMC_PreEnterLowPowerMode(void)

Prepares to enter low power modes.

This function should be called before entering low power modes.

void CMC_PostExitLowPowerMode(void)

Recovers after wake up from low power modes.

This function should be called after wake up from low power modes. This function should be used with *CMC_PreEnterLowPowerMode()*

void CMC_GlobalEnterLowPowerMode(CMC_Type *base, *cmc_low_power_mode_t* lowPowerMode)

Configs the entry into the same low power mode for each power domains.

This function provides the feature to entry into the same low power mode for each power domains. Before invoking this function, please ensure the selected power mode have been allowed.

Parameters

- base – CMC peripheral base address.
- lowPowerMode – The low power mode to be entered. See *cmc_low_power_mode_t* for the details.

void CMC_EnterLowPowerMode(CMC_Type *base, const *cmc_power_domain_config_t* *config)

Configs the entry into different low power modes for each power domains.

This function provides the feature to entry into different low power modes for each power domains. Before invoking this function please ensure the selected modes are allowed.

Parameters

- base – CMC peripheral base address.
- config – Pointer to the cmc_power_domain_config_t structure.

bool lowpowerFilterEnable
: Low Power Filter enable.

bool resetFilterEnable
: Reset Filter enable.

uint8_t resetFilterWidth
: Width of the Reset Filter.

cmc_clock_mode_t clock_mode
: Clock mode for each power domain.

cmc_low_power_mode_t main_domain
: The low power mode of the MAIN power domain.

struct __cmc_reset_pin_config
: *#include <fsl_cmc.h>* CMC reset pin configuration.

struct __cmc_power_domain_config
: *#include <fsl_cmc.h>* power mode configuration for each power domain.

2.62 MCX_SPC: System Power Control driver

uint8_t SPC_GetPeriphIOIsolationStatus(SPC_Type *base)
: Gets Isolation status for each power domains.

  This function gets the status which indicates whether certain peripheral and the IO pads are in a latched state as a result of having been in POWERDOWN mode.

  Parameters

  - base – SPC peripheral base address.

  Returns
  Current isolation status for each power domains. See *_spc_power_domains* for details.

static inline void SPC_ClearPeriphIOIsolationFlag(SPC_Type *base)
: Clears peripherals and I/O pads isolation flags for each power domains.

  This function clears peripherals and I/O pads isolation flags for each power domains. After recovering from the POWERDOWN mode, user must invoke this function to release the I/O pads and certain peripherals to their normal run mode state. Before invoking this function, user must restore chip configuration in particular pin configuration for enabled WUU wakeup pins.

  Parameters

  - base – SPC peripheral base address.

static inline bool SPC_GetBusyStatusFlag(SPC_Type *base)
: Gets SPC busy status flag.

  This function gets SPC busy status flag. When SPC executing any type of power mode transition in ACTIVE mode or any of the SOC low power mode, the SPC busy status flag is set and this function returns true. When changing CORE LDO voltage level and DCDC voltage level in ACTIVE mode, the SPC busy status flag is set and this function return true.

Parameters

- base – SPC peripheral base address.

Returns
Ack busy flag. true - SPC is busy. false - SPC is not busy.

static inline bool SPC_CheckLowPowerReqest(SPC_Type *base)

Checks system low power request.

Note: Only when all power domains request low power mode entry, the result of this function is true. That means when all power domains request low power mode entry, the SPC regulators will be controlled by LP_CFG register.

Parameters

- base – SPC peripheral base address.

Returns
The system low power request check result.

- **true** All power domains have requested low power mode and SPC has entered a low power state and power mode configuration are based on the LP_CFG configuration register.
- **false** SPC in active mode and ACTIVE_CFG register control system power supply.

static inline void SPC_ClearLowPowerRequest(SPC_Type *base)

Clears system low power request, set SPC in active mode.

Parameters

- base – SPC peripheral base address.

static inline *spc_power_domain_low_power_mode_t* SPC_GetRequestedLowPowerMode(SPC_Type *base)

Check the last low-power mode that the power domain requested.

Parameters

- base – SPC peripheral base address.

Returns
The last low-power mode that the power domain requested.

static inline bool SPC_CheckSwitchState(SPC_Type *base)

Checks whether the power switch is on.

Parameters

- base – SPC peripheral base address.

Return values

- true – The power switch is on.
- false – The power switch is off.

spc_power_domain_low_power_mode_t SPC_GetPowerDomainLowPowerMode(SPC_Type *base, *spc_power_domain_id_t* powerDomainId)

Gets selected power domain's requested low power mode.

Parameters

- base – SPC peripheral base address.
- powerDomainId – Power Domain Id, please refer to *spc_power_domain_id_t*.

Returns

The selected power domain's requested low power mode, please refer to *spc_power_domain_low_power_mode_t*.

static inline bool SPC_CheckPowerDomainLowPowerRequest(SPC_Type *base, *spc_power_domain_id_t* powerDomainId)

Checks power domain's low power request.

Parameters

- base – SPC peripheral base address.
- powerDomainId – Power Domain Id, please refer to *spc_power_domain_id_t*.

Returns

The result of power domain's low power request.

- **true** The selected power domain requests low power mode entry.
- **false** The selected power domain does not request low power mode entry.

static inline void SPC_ClearPowerDomainLowPowerRequestFlag(SPC_Type *base, *spc_power_domain_id_t* powerDomainId)

Clears selected power domain's low power request flag.

Parameters

- base – SPC peripheral base address.
- powerDomainId – Power Domain Id, please refer to *spc_power_domain_id_t*.

static inline void SPC_TrimSRAMLdoRefVoltage(SPC_Type *base, uint8_t trimValue)

Trims SRAM retention regulator reference voltage, trim step is 12 mV, range is around 0.48V to 0.85V.

Parameters

- base – SPC peripheral base address.
- trimValue – Reference voltage trim value.

static inline void SPC_EnableSRAMLdo(SPC_Type *base, bool enable)

Enables/disables SRAM retention LDO.

Parameters

- base – SPC peripheral base address.
- enable – Used to enable/disable SRAM LDO :
  - **true** Enable SRAM LDO;
  - **false** Disable SRAM LDO.

static inline void SPC_RetainSRAMArray(SPC_Type *base, uint8_t mask)

Parameters

- base – SPC peripheral base address.
- mask – The OR'ed value of SRAM Array.

static inline void SPC_UnRetainSRAMArray(SPC_Type *base, uint8_t mask)

Unretain SRAM array.

Parameters

- base – SPC peripheral base address.
- mask – The OR'ed value of SRAM Array.

void SPC_SetLowPowerRequestConfig(SPC_Type *base, const *spc_lowpower_request_config_t* *config)

Configs Low power request output pin.

This function config the low power request output pin

Parameters

- base – SPC peripheral base address.
- config – Pointer the *spc_lowpower_request_config_t* structure.

static inline void SPC_EnableIntegratedPowerSwitchManually(SPC_Type *base, bool enable)

Enables/disables the integrated power switch manually.

Parameters

- base – SPC peripheral base address.
- enable – Used to enable/disable the integrated power switch:
  - **true** Enable the integrated power switch;
  - **false** Disable the integrated power switch.

static inline void SPC_EnableIntegratedPowerSwitchAutomatically(SPC_Type *base, bool sleepGate, bool wakeupUngate)

Enables/disables the integrated power switch automatically.

To gate the integrated power switch when chip enter low power modes, and ungate the switch after wake-up from low power modes:

```
SPC_EnableIntegratedPowerSwitchAutomatically(SPC, true, true);
```

Parameters

- base – SPC peripheral base address.
- sleepGate – Enable the integrated power switch when chip enter low power modes:
  - **true** SPC asserts an output pin at low-power entry to power-gate the switch;
  - **false** SPC does not assert an output pin at low-power entry to power-gate the switch.
- wakeupUngate – Enables the switch after wake-up from low power modes:
  - **true** SPC asserts an output pin at low-power exit to power-ungate the switch;
  - **false** SPC does not assert an output pin at low-power exit to power-ungate the switch.

void SPC_SetSRAMOperateVoltage(SPC_Type *base, const *spc_sram_voltage_config_t* *config)

Set SRAM operate voltage.

Parameters

- base – SPC peripheral base address.
- config – The pointer to *spc_sram_voltage_config_t*, specifies the configuration of sram voltage.

static inline *spc_bandgap_mode_t* SPC_GetActiveModeBandgapMode(SPC_Type *base)

Gets the Bandgap mode in Active mode.

Parameters

- base – SPC peripheral base address.

Returns

Bandgap mode in the type of *spc_bandgap_mode_t* enumeration.

static inline uint32_t SPC_GetActiveModeVoltageDetectStatus(SPC_Type *base)

Gets all voltage detectors status in Active mode.

Parameters

- base – SPC peripheral base address.

Returns

All voltage detectors status in Active mode.

status_t SPC_SetActiveModeBandgapModeConfig(SPC_Type *base, *spc_bandgap_mode_t* mode)

Configs Bandgap mode in Active mode.

Note: To disable bandgap in Active mode:

a. Disable all LVD's and HVD's in active mode;

b. Disable Glitch detect;

c. Configrue LDO's and DCDC to low drive strength in active mode;

d. Invoke this function to disable bandgap in active mode; otherwise the error status will be reported.

Note: Some other system resources(such as PLL, CMP) require bandgap to be enabled, to disable bandgap please take care of other system resources.

Parameters

- base – SPC peripheral base address.
- mode – The Bandgap mode be selected.

Return values

- kStatus_SPC_BandgapModeWrong – The Bandgap can not be disabled in active mode.
- kStatus_Success – Config Bandgap mode in Active power mode successful.

static inline void SPC_EnableActiveModeCMPBandgapBuffer(SPC_Type *base, bool enable)

Enables/Disable the CMP Bandgap Buffer in Active mode.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable CMP Bandgap buffer. true - Enable Buffer Stored Reference voltage to CMP. false - Disable Buffer Stored Reference voltage to CMP.

static inline void SPC_SetActiveModeVoltageTrimDelay(SPC_Type *base, uint16_t delay)

Sets the delay when the regulators change voltage level in Active mode.

Parameters

- base – SPC peripheral base address.
- delay – The number of SPC timer clock cycles.

status_t SPC_SetActiveModeRegulatorsConfig(SPC_Type *base, const *spc_active_mode_regulators_config_t* *config)

Configs all settings of regulators in Active mode at a time.

Note: This function is used to overwrite all settings of regulators(including bandgap mode, regulators' drive strength and voltage level) in active mode at a time.

Note: Enable/disable LVDs/HVDs before invoking this function.

Note: This function will check input parameters based on hardware restrictions before setting registers, if input parameters do not satisfy hardware restrictions the specific error will be reported.

Note: Some hardware restrictions not covered, application should be aware of this and follow this hardware restrictions otherwise some unkown issue may occur:

a. If Core LDO's drive strength are set to same value in both Active mode and low power mode, the voltage level should also set to same value.

b. When switching Core LDO's drive strength from low to normal, ensure the LDO_CORE high voltage level is set to same level that was set prior to switching to the LDO_CORE drive strength. Otherwise, if the LVDs are enabled, an unexpected LVD can occur.

Note: If this function can not satisfy some tricky settings, please invoke other APIs in low-level function group.

Parameters

- base – SPC peripheral base address.
- config – Pointer to spc_active_mode_regulators_config_t structure.

Return values

- kStatus_Success – Config regulators in Active power mode successful.
- kStatus_SPC_BandgapModeWrong – Based on input setting, bandgap can not be disabled.
- kStatus_SPC_Busy – The SPC instance is busy to execute any type of power mode transition.

- kStatus_SPC_CORELDOLowDriveStrengthIgnore – Any of LVDs/HVDs kept enabled before invoking this function.
- kStatus_SPC_SYSLDOOverDriveVoltageFail – Fail to regulator to Over Drive Voltage due to System VDD HVD is not disabled.
- kStatus_SPC_SYSLDOLowDriveStrengthIgnore – Any of LVDs/HVDs kept enabled before invoking this function.
- kStatus_SPC_CORELDOVoltageWrong – Core LDO and System LDO do not have same voltage level.

static inline void SPC_EnableActiveModeAnalogModules(SPC_Type *base, uint32_t maskValue)

Enables analog modules in active mode.

Parameters

- base – SPC peripheral base address.
- maskValue – The mask of analog modules to enable in active mode, should be the OR'ed value of *spc_analog_module_control*.

static inline void SPC_DisableActiveModeAnalogModules(SPC_Type *base, uint32_t maskValue)

Disables analog modules in active mode.

Parameters

- base – SPC peripheral base address.
- maskValue – The mask of analog modules to disable in active mode, should be the OR'ed value of *spc_analog_module_control*.

static inline uint32_t SPC_GetActiveModeEnabledAnalogModules(SPC_Type *base)

Gets enabled analog modules that enabled in active mode.

Parameters

- base – SPC peripheral base address.

Returns

The mask of enabled analog modules that enabled in active mode.

static inline *spc_bandgap_mode_t* SPC_GetLowPowerModeBandgapMode(SPC_Type *base)

Gets the Bandgap mode in Low Power mode.

Parameters

- base – SPC peripheral base address.

Returns

Bandgap mode in the type of *spc_bandgap_mode_t* enumeration.

static inline uint32_t SPC_GetLowPowerModeVoltageDetectStatus(SPC_Type *base)

Gets the status of all voltage detectors in Low Power mode.

Parameters

- base – SPC peripheral base address.

Returns

The status of all voltage detectors in low power mode.

static inline void SPC_EnableLowPowerModeLowPowerIREF(SPC_Type *base, bool enable)

Enables/Disables Low Power IREF in low power modes.

This function enables/disables Low Power IREF. Low Power IREF can only get disabled in Deep power down mode. In other low power modes, the Low Power IREF is always enabled.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable Low Power IREF. true - Enable Low Power IREF for Low Power modes. false - Disable Low Power IREF for Deep Power Down mode.

status_t SPC_SetLowPowerModeBandgapmodeConfig(SPC_Type *base, *spc_bandgap_mode_t* mode)

Configs Bandgap mode in Low Power mode.

Note: To disable Bandgap in Low-power mode:

a. Disable all LVD's ad HVD's in low power mode;

b. Disable Glitch detect in low power mode;

c. Configure LDO's and DCDC to low drive strength in low power mode;

d. Disable bandgap in low power mode; Otherwise, the error status will be reported.

Note: Some other system resources(such as PLL, CMP) require bandgap to be enabled, to disable bandgap please take care of other system resources.

Parameters

- base – SPC peripheral base address.
- mode – The Bandgap mode be selected.

Return values

- kStatus_SPC_BandgapModeWrong – The bandgap mode setting in Low Power mode is wrong.
- kStatus_Success – Config Bandgap mode in Low Power power mode successful.

static inline void SPC_EnableSRAMLdOLowPowerModeIREF(SPC_Type *base, bool enable)

Enables/disables SRAM_LDO deep power low power IREF.

Parameters

- base – SPC peripheral base address.
- enable – Used to enable/disable low power IREF :
  - **true:** Low Power IREF is enabled ;
  - **false:** Low Power IREF is disabled for power saving.

static inline void SPC_EnableLowPowerModeCMPBandgapBufferMode(SPC_Type *base, bool enable)

Enables/Disables CMP Bandgap Buffer.

This function gates CMP bandgap buffer. CMP bandgap buffer is automatically disabled and turned off in Deep Power Down mode.

Deprecated:

No longer used, please use SPC_EnableLowPowerModeCMPBandgapBuffer as instead.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable CMP Bandgap buffer. true - Enable Buffer Stored Reference Voltage to CMP. false - Disable Buffer Stored Reference Voltage to CMP.

static inline void SPC_EnableLowPowerModeCMPBandgapBuffer(SPC_Type *base, bool enable)

Enables/Disables CMP Bandgap Buffer.

This function gates CMP bandgap buffer. CMP bandgap buffer is automatically disabled and turned off in Deep Power Down mode.

Deprecated:

No longer used.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable CMP Bandgap buffer. true - Enable Buffer Stored Reference Voltage to CMP. false - Disable Buffer Stored Reference Voltage to CMP.

static inline void SPC_EnableLowPowerModeCoreVDDInternalVoltageScaling(SPC_Type *base, bool enable)

Enables/Disables CORE VDD IVS(Internal Voltage Scaling) in power down modes.

This function gates CORE VDD IVS. When enabled, the IVS regulator will scale the external input CORE VDD to a lower voltage level to reduce internal leakage. IVS is invalid in Sleep or Deep power down mode.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable IVS. true - enable CORE VDD IVS in Power Down mode. false - disable CORE VDD IVS in Power Down mode.

static inline void SPC_SetLowPowerWakeUpDelay(SPC_Type *base, uint16_t delay)

Sets the delay when exit the low power modes.

Parameters

- base – SPC peripheral base address.
- delay – The number of SPC timer clock cycles that the SPC waits on exit from low power modes.

status_t SPC_SetLowPowerModeRegulatorsConfig(SPC_Type *base, const *spc_lowpower_mode_regulators_config_t* *config)

Configs all settings of regulators in Low power mode at a time.

Note: This function is used to overwrite all settings of regulators(including bandgap mode, regulators' drive strength and voltage level) in low power mode at a time.

Note: Enable/disable LVDs/HVDs before invoking this function.

Note: This function will check input parameters based on hardware restrictions before setting registers, if input parameters do not satisfy hardware restrictions the specific error will be reported.

Note: Some hardware restrictions not covered, application should be aware of this and follow this hardware restrictions otherwise some unkown issue may occur:

a. If Core LDO's drive strength are set to same value in both Active mode and low power mode, the voltage level should also set to same value.

b. When switching Core LDO's drive strength from low to normal, ensure the LDO_CORE high voltage level is set to same level that was set prior to switching to the LDO_CORE drive strength. Otherwise, if the LVDs are enabled, an unexpected LVD can occur.

Note: If this function can not satisfy some tricky settings, please invoke other APIs in low-level function group.

Parameters

- base – SPC peripheral base address.
- config – Pointer to spc_lowpower_mode_regulators_config_t structure.

Return values

- kStatus_Success – Config regulators in Low power mode successful.
- kStatus_SPC_BandgapModeWrong – The bandgap should not be disabled based on input settings.
- kStatus_SPC_CORELDOLowDriveStrengthIgnore – Set driver strength to low will be ignored.
- kStatus_SPC_SYSLDOLowDriveStrengthIgnore – Set driver strength to low will be ignored.
- kStatus_SPC_CORELDOVoltageWrong – Core LDO and System LDO do not have same voltage level.

static inline void SPC_EnableLowPowerModeAnalogModules(SPC_Type *base, uint32_t maskValue)

Enables analog modules in low power modes.

Parameters

- base – SPC peripheral base address.
- maskValue – The mask of analog modules to enable in low power modes, should be OR'ed value of *spc_analog_module_control*.

static inline void SPC_DisableLowPowerModeAnalogModules(SPC_Type *base, uint32_t maskValue)

Disables analog modules in low power modes.

Parameters

- base – SPC peripheral base address.
- maskValue – The mask of analog modules to disable in low power modes, should be OR'ed value of *spc_analog_module_control*.

static inline uint32_t SPC_GetLowPowerModeEnabledAnalogModules(SPC_Type *base)

Gets enabled analog modules that enabled in low power modes.

Parameters

- base – SPC peripheral base address.

Returns

The mask of enabled analog modules that enabled in low power modes.

static inline uint32_t SPC_GetVoltageDetectStatusFlag(SPC_Type *base)

Get Voltage Detect Status Flags.

Parameters

- base – SPC peripheral base address.

Returns

Voltage Detect Status Flags. See *_spc_voltage_detect_flags* for details.

static inline void SPC_ClearVoltageDetectStatusFlag(SPC_Type *base, uint8_t mask)

Clear Voltage Detect Status Flags.

Parameters

- base – SPC peripheral base address.
- mask – The mask of the voltage detect status flags. See *_spc_voltage_detect_flags* for details.

void SPC_SetCoreVoltageDetectConfig(SPC_Type *base, const *spc_core_voltage_detect_config_t* *config)

Configs CORE voltage detect options.

Note: : Setting both the voltage detect interrupt and reset enable will cause interrupt to be generated on exit from reset. If those conditioned is not desired, interrupt/reset so only one is enabled.

Parameters

- base – SPC peripheral base address.
- config – Pointer to spc_core_voltage_detect_config_t structure.

static inline void SPC_LockCoreVoltageDetectResetSetting(SPC_Type *base)

Locks Core voltage detect reset setting.

This function locks core voltage detect reset setting. After invoking this function any configuration of Core voltage detect reset will be ignored.

Parameters

- base – SPC peripheral base address.

static inline void SPC_UnlockCoreVoltageDetectResetSetting(SPC_Type *base)

Unlocks Core voltage detect reset setting.

This function unlocks core voltage detect reset setting. If locks the Core voltage detect reset setting, invoking this function to unlock.

Parameters

- base – SPC peripheral base address.

status_t SPC_EnableActiveModeCoreLowVoltageDetect(SPC_Type *base, bool enable)

Enables/Disables the Core Low Voltage Detector in Active mode.

Note: If the CORE_LDO low voltage detect is enabled in Active mode, please note that the bandgap must be enabled and the drive strength of each regulator must not set to low.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable Core LVD. true - Enable Core Low voltage detector in active mode. false - Disable Core Low voltage detector in active mode.

Return values

kStatus_Success – Enable/Disable Core Low Voltage Detect successfully.

status_t SPC_EnableLowPowerModeCoreLowVoltageDetect(SPC_Type *base, bool enable)

Enables/Disables the Core Low Voltage Detector in Low Power mode.

This function enables/disables the Core Low Voltage Detector. If enabled the Core Low Voltage detector. The Bandgap mode in low power mode must be programmed so that Bandgap is enabled.

Note: If the CORE_LDO low voltage detect is enabled in Low Power mode, please note that the bandgap must be enabled and the drive strength of each regulator must not set to low in Low Power mode.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable Core HVD. true - Enable Core Low voltage detector in low power mode. false - Disable Core Low voltage detector in low power mode.

Return values

kStatus_Success – Enable/Disable Core Low Voltage Detect in low power mode successfully.

status_t SPC_EnableActiveModeCoreHighVoltageDetect(SPC_Type *base, bool enable)

Enables/Disables the Core High Voltage Detector in Active mode.

Note: If the CORE_LDO high voltage detect is enabled in Active mode, please note that the bandgap must be enabled and the drive strength of each regulator must not set to low.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable Core HVD. true - Enable Core High voltage detector in active mode. false - Disable Core High voltage detector in active mode.

Return values

kStatus_Success – Enable/Disable Core High Voltage Detect successfully.

status_t SPC_EnableLowPowerModeCoreHighVoltageDetect(SPC_Type *base, bool enable)

Enables/Disables the Core High Voltage Detector in Low Power mode.

This function enables/disables the Core High Voltage Detector. If enabled the Core High Voltage detector. The Bandgap mode in low power mode must be programmed so that Bandgap is enabled.

Note: If the CORE_LDO high voltage detect is enabled in Low Power mode, please note that the bandgap must be enabled and the drive strength of each regulator must not set to low in low power mode.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable Core HVD. true - Enable Core High voltage detector in low power mode. false - Disable Core High voltage detector in low power mode.

Return values

kStatus_Success – Enable/Disable Core High Voltage Detect in low power mode successfully.

void SPC_SetSystemVDDLowVoltageLevel(SPC_Type *base, *spc_low_voltage_level_select_t* level)

Set system VDD Low-voltage level selection.

This function selects the system VDD low-voltage level. Changing system VDD low-voltage level must be done after disabling the System VDD low voltage reset and interrupt.

Deprecated:

In latest RM, reserved for all devices, will removed in next release.

Parameters

- base – SPC peripheral base address.
- level – System VDD Low-Voltage level selection.

void SPC_SetSystemVoltageDetectConfig(SPC_Type *base, const *spc_system_voltage_detect_config_t* *config)

Configs SYS voltage detect options.

This function config SYS voltage detect options.

Note: : Setting both the voltage detect interrupt and reset enable will cause interrupt to be generated on exit from reset. If those conditioned is not desired, interrupt/reset so only one is enabled.

Parameters

- base – SPC peripheral base address.
- config – Pointer to spc_system_voltage_detect_config_t structure.

static inline void SPC_LockSystemVoltageDetectResetSetting(SPC_Type *base)

Lock System voltage detect reset setting.

This function locks system voltage detect reset setting. After invoking this function any configuration of System Voltage detect reset will be ignored.

Parameters

- base – SPC peripheral base address.

static inline void SPC_UnlockSystemVoltageDetectResetSetting(SPC_Type *base)

Unlock System voltage detect reset setting.

This function unlocks system voltage detect reset setting. If locks the System voltage detect reset setting, invoking this function to unlock.

Parameters

- base – SPC peripheral base address.

status_t SPC_EnableActiveModeSystemHighVoltageDetect(SPC_Type *base, bool enable)

Enables/Disables the System High Voltage Detector in Active mode.

Note: If the System_LDO high voltage detect is enabled in Active mode, please note that the bandgap must be enabled and the drive strength of each regulator must not set to low in Active mode.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable System HVD. true - Enable System High voltage detector in active mode. false - Disable System High voltage detector in active mode.

Return values

kStatus_Success – Enable/Disable System High Voltage Detect successfully.

status_t SPC_EnableActiveModeSystemLowVoltageDetect(SPC_Type *base, bool enable)

Enables/Disable the System Low Voltage Detector in Active mode.

Note: If the System_LDO low voltage detect is enabled in Active mode, please note that the bandgap must be enabled and the drive strength of each regulator must not set to low in Active mode.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable System LVD. true - Enable System Low voltage detector in active mode. false - Disable System Low voltage detector in active mode.

Return values

kStatus_Success – Enable/Disable the System Low Voltage Detect successfully.

status_t SPC_EnableLowPowerModeSystemHighVoltageDetect(SPC_Type *base, bool enable)

Enables/Disables the System High Voltage Detector in Low Power mode.

Note: If the System_LDO high voltage detect is enabled in Low Power mode, please note that the bandgap must be enabled and the drive strength of each regulator must not set to low in Low Power mode.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable System HVD. true - Enable System High voltage detector in low power mode. false - Disable System High voltage detector in low power mode.

Return values

kStatus_Success – Enable/Disable System High Voltage Detect in low power mode successfully.

status_t SPC_EnableLowPowerModeSystemLowVoltageDetect(SPC_Type *base, bool enable)

Enables/Disables the System Low Voltage Detector in Low Power mode.

Note: If the System_LDO low voltage detect is enabled in Low Power mode, please note that the bandgap must be enabled and the drive strength of each regulator must not set to low in Low Power mode.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable System HVD. true - Enable System Low voltage detector in low power mode. false - Disable System Low voltage detector in low power mode.

Return values

kStatus_Success – Enables System Low Voltage Detect in low power mode successfully.

void SPC_SetIOVDDLowVoltageLevel(SPC_Type *base, *spc_low_voltage_level_select_t* level)

Set IO VDD Low-Voltage level selection.

This function selects the IO VDD Low-voltage level. Changing IO VDD low-voltage level must be done after disabling the IO VDD low voltage reset and interrupt.

Parameters

- base – SPC peripheral base address.
- level – IO VDD Low-voltage level selection.

void SPC_SetIOVoltageDetectConfig(SPC_Type *base, const *spc_io_voltage_detect_config_t* *config)

Configs IO voltage detect options.

This function config IO voltage detect options.

Note: : Setting both the voltage detect interrupt and reset enable will cause interrupt to be generated on exit from reset. If those conditioned is not desired, interrupt/reset so only one is enabled.

Parameters

- base – SPC peripheral base address.
- config – Pointer to spc_voltage_detect_config_t structure.

static inline void SPC_LockIOVoltageDetectResetSetting(SPC_Type *base)

Lock IO Voltage detect reset setting.

This function locks IO voltage detect reset setting. After invoking this function any configuration of system voltage detect reset will be ignored.

Parameters

- base – SPC peripheral base address.

static inline void SPC_UnlockIOVoltageDetectResetSetting(SPC_Type *base)

Unlock IO voltage detect reset setting.

This function unlocks IO voltage detect reset setting. If locks the IO voltage detect reset setting, invoking this function to unlock.

Parameters

- base – SPC peripheral base address.

status_t SPC_EnableActiveModeIOHighVoltageDetect(SPC_Type *base, bool enable)

Enables/Disables the IO High Voltage Detector in Active mode.

Note: If the IO high voltage detect is enabled in Active mode, please note that the bandgap must be enabled and the drive strength of each regulator must not set to low in Active mode.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable IO HVD. true - Enable IO High voltage detector in active mode. false - Disable IO High voltage detector in active mode.

Return values

kStatus_Success – Enable/Disable IO High Voltage Detect successfully.

status_t SPC_EnableActiveModeIOLowVoltageDetect(SPC_Type *base, bool enable)

Enables/Disables the IO Low Voltage Detector in Active mode.

Note: If the IO low voltage detect is enabled in Active mode, please note that the bandgap must be enabled and the drive strength of each regulator must not set to low in Active mode.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable IO LVD. true - Enable IO Low voltage detector in active mode. false - Disable IO Low voltage detector in active mode.

Return values

kStatus_Success – Enable IO Low Voltage Detect successfully.

status_t SPC_EnableLowPowerModeIOHighVoltageDetect(SPC_Type *base, bool enable)

Enables/Disables the IO High Voltage Detector in Low Power mode.

Note: If the IO high voltage detect is enabled in Low Power mode, please note that the bandgap must be enabled and the drive strength of each regulator must not set to low in Low Power mode.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable IO HVD. true - Enable IO High voltage detector in low power mode. false - Disable IO High voltage detector in low power mode.

Return values

kStatus_Success – Enable IO High Voltage Detect in low power mode successfully.

status_t SPC_EnableLowPowerModeIOLowVoltageDetect(SPC_Type *base, bool enable)

Enables/Disables the IO Low Voltage Detector in Low Power mode.

Note: If the IO low voltage detect is enabled in Low Power mode, please note that the bandgap must be enabled and the drive strength of each regulator must not set to low in Low Power mode.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable IO LVD. true - Enable IO Low voltage detector in low power mode. false - Disable IO Low voltage detector in low power mode.

Return values

kStatus_Success – Enable/Disable IO Low Voltage Detect in low power mode successfully.

void SPC_SetExternalVoltageDomainsConfig(SPC_Type *base, uint8_t lowPowerIsoMask, uint8_t IsoMask)

Configs external voltage domains.

This function configs external voltage domains isolation.

Parameters

- base – SPC peripheral base address.
- lowPowerIsoMask – The mask of external domains isolate enable during low power mode. Please read the Reference Manual for the Bitmap.
- IsoMask – The mask of external domains isolate. Please read the Reference Manual for the Bitmap.

static inline uint8_t SPC_GetExternalDomainsStatus(SPC_Type *base)

Gets External Domains status.

Parameters

- base – SPC peripheral base address.

Returns

The status of each external domain.

static inline void SPC_EnableCoreLDORegulator(SPC_Type *base, bool enable)

Enable/Disable Core LDO regulator.

Note: The CORE LDO enable bit is write-once.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable CORE LDO Regulator. true - Enable CORE LDO Regulator. false - Disable CORE LDO Regulator.

static inline void SPC_PullDownCoreLDORegulator(SPC_Type *base, bool pulldown)

Enable/Disable the CORE LDO Regulator pull down in Deep Power Down.

Note: This function only useful when enabled the CORE LDO Regulator.

Parameters

- base – SPC peripheral base address.
- pulldown – Enable/Disable CORE LDO pulldown in Deep Power Down mode. true - CORE LDO Regulator will discharge in Deep Power Down mode. false - CORE LDO Regulator will not discharge in Deep Power Down mode.

status_t SPC_SetActiveModeCoreLDORegulatorConfig(SPC_Type *base, const *spc_active_mode_core_ldo_option_t* *option)

Configs Core LDO Regulator in Active mode.

Note: The bandgap must be enabled before invoking this function.

Note: To set Core LDO as low drive strength, all HVDs/LVDs must be disabled previously.

Parameters

- base – SPC peripheral base address.
- option – Pointer to the spc_active_mode_core_ldo_option_t structure.

Return values

- kStatus_Success – Config Core LDO regulator in Active power mode successful.
- kStatus_SPC_Busy – The SPC instance is busy to execute any type of power mode transition.
- kStatus_SPC_BandgapModeWrong – Bandgap should be enabled before invoking this function.
- kStatus_SPC_CORELDOLowDriveStrengthIgnore – To set Core LDO as low drive strength, all LVDs/HVDs must be disabled before invoking this function.

status_t SPC_SetActiveModeCoreLDORegulatorVoltageLevel(SPC_Type *base, *spc_core_ldo_voltage_level_t* voltageLevel)

Set Core LDO Regulator Voltage level in Active mode.

Note: In active mode, the Core LDO voltage level should only be changed when the Core LDO is in normal drive strength.

Note: Update Core LDO voltage level will set Busy flag, this function return only when busy flag is cleared by hardware

Parameters

- base – SPC peripheral base address.
- voltageLevel – Specify the voltage level of CORE LDO Regulator in Active mode, please refer to *spc_core_ldo_voltage_level_t*.

Return values

- kStatus_SPC_CORELDOVoltageSetFail – The drive strength of Core LDO is not normal.
- kStatus_Success – Set Core LDO regulator voltage level in Active power mode successful.

static inline *spc_core_ldo_voltage_level_t* SPC_GetActiveModeCoreLDOVDDVoltageLevel(SPC_Type *base)

Gets CORE LDO Regulator Voltage level.

This function returns the voltage level of CORE LDO Regulator in Active mode.

Parameters

- base – SPC peripheral base address.

Returns

Voltage level of CORE LDO in type of *spc_core_ldo_voltage_level_t* enumeration.

status_t SPC_SetActiveModeCoreLDORegulatorDriveStrength(SPC_Type *base, *spc_core_ldo_drive_strength_t* driveStrength)

Set Core LDO VDD Regulator Drive Strength in Active mode.

Parameters

- base – SPC peripheral base address.
- driveStrength – Specify the drive strength of CORE LDO Regulator in Active mode, please refer to *spc_core_ldo_drive_strength_t*.

Return values

- kStatus_Success – Set Core LDO regulator drive strength in Active power mode successful.
- kStatus_SPC_CORELDOLowDriveStrengthIgnore – If any voltage detect enabled, core_ldo's drive strength can not set to low.
- kStatus_SPC_BandgapModeWrong – The selected bandgap mode is not allowed.

static inline *spc_core_ldo_drive_strength_t* SPC_GetActiveModeCoreLDODriveStrength(SPC_Type *base)

Gets CORE LDO VDD Regulator Drive Strength in Active mode.

Parameters

- base – SPC peripheral base address.

Returns

Drive Strength of CORE LDO regulator in Active mode, please refer to *spc_core_ldo_drive_strength_t*.

status_t SPC_SetLowPowerModeCoreLDORegulatorConfig(SPC_Type *base, const *spc_lowpower_mode_core_ldo_option_t* *option)

Configs CORE LDO Regulator in low power mode.

This function configs CORE LDO Regulator in Low Power mode. If CORE LDO VDD Drive Strength is set to Normal, the CORE LDO VDD regulator voltage level in Active mode must be equal to the voltage level in Low power mode. And the Bandgap must be programmed to select bandgap enabled. Core VDD voltage levels for the Core LDO low power regulator can only be changed when the CORE LDO Drive Strength set as Normal.

Parameters

- base – SPC peripheral base address.
- option – Pointer to the spc_lowpower_mode_core_ldo_option_t structure.

Return values

- kStatus_Success – Config Core LDO regulator in power mode successfully.
- kStatus_SPC_Busy – The SPC instance is busy to execute any type of power mode transition.
- kStatus_SPC_CORELDOLowDriveStrengthIgnore – Set driver strength to low will be ignored.
- #kStatus_SPC_CORELDOVoltageSetFail. – Fail to change Core LDO voltage level.

status_t SPC_SetLowPowerModeCoreLDORegulatorVoltageLevel(SPC_Type *base, *spc_core_ldo_voltage_level_t* voltageLevel)

Set Core LDO VDD Regulator Voltage level in Low power mode.

Note: If CORE LDO's drive strength is set to Normal, the CORE LDO VDD regulator voltage in active mode and low power mode must be same.

Note: Voltage level for the CORE LDO in low power mode can only be changed when the CORE LDO Drive Strength set as Normal.

Parameters

- base – SPC peripheral base address.
- voltageLevel – Voltage level of CORE LDO Regulator in Low power mode, please refer to *spc_core_ldo_voltage_level_t*.

Return values

- kStatus_SPC_CORELDOVoltageWrong – Voltage level in active mode and low power mode is not same.
- kStatus_Success – Set Core LDO regulator voltage level in Low power mode successful.
- kStatus_SPC_CORELDOVoltageSetFail – Fail to update voltage level because drive strength is incorrect.

static inline *spc_core_ldo_voltage_level_t* SPC_GetLowPowerCoreLDOVDDVoltageLevel(SPC_Type *base)

Gets the CORE LDO VDD Regulator Voltage Level for Low Power modes.

Parameters

- base – SPC peripheral base address.

Returns

The CORE LDO VDD Regulator's voltage level.

status_t SPC_SetLowPowerModeCoreLDORegulatorDriveStrength(SPC_Type *base, *spc_core_ldo_drive_strength_t* driveStrength)

Set Core LDO VDD Regulator Drive Strength in Low power mode.

Parameters

- base – SPC peripheral base address.
- driveStrength – Specify drive strength of CORE LDO in low power mode.

Return values

- kStatus_SPC_CORELDOLowDriveStrengthIgnore – Some voltage detect enabled, CORE LDO's drive strength can not set as low.
- kStatus_Success – Set Core LDO regulator drive strength in Low power mode successful.
- kStatus_SPC_BandgapModeWrong – Bandgap is disabled when attempt to set CORE LDO work as normal drive strength.

static inline *spc_core_ldo_drive_strength_t* SPC_GetLowPowerCoreLDOVDDDriveStrength(SPC_Type *base)

Gets CORE LDO VDD Drive Strength for Low Power modes.

Parameters

- base – SPC peripheral base address.

Returns

The CORE LDO's VDD Drive Strength.

static inline void SPC_EnableSystemLDORegulator(SPC_Type *base, bool enable)

Enable/Disable System LDO regulator.

Note: The SYSTEM LDO enable bit is write-once.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable System LDO Regulator. true - Enable System LDO Regulator. false - Disable System LDO Regulator.

static inline void SPC_EnableSystemLDOSinkFeature(SPC_Type *base, bool sink)

Enable/Disable current sink feature of System LDO Regulator.

Parameters

- base – SPC peripheral base address.
- sink – Enable/Disable current sink feature. true - Enable current sink feature of System LDO Regulator. false - Disable current sink feature of System LDO Regulator.

status_t SPC_SetActiveModeSystemLDORegulatorConfig(SPC_Type *base, const *spc_active_mode_sys_ldo_option_t* *option)

Configs System LDO VDD Regulator in Active mode.

Note: If System LDO VDD Drive Strength is set to Normal, the Bandgap mode in Active mode must be programmed to a value that enables the bandgap.

Note: If any voltage detects are kept enabled, configuration to set System LDO VDD drive strength to low will be ignored.

Note: If select System LDO VDD Regulator voltage level to Over Drive Voltage, the Drive Strength of System LDO VDD Regulator must be set to Normal otherwise the regulator Drive Strength will be forced to Normal.

Note: If select System LDO VDD Regulator voltage level to Over Drive Voltage, the High voltage detect must be disabled. Otherwise it will be fail to regulator to Over Drive Voltage.

Parameters

- base – SPC peripheral base address.
- option – Pointer to the spc_active_mode_sys_ldo_option_t structure.

Return values

- kStatus_Success – Config System LDO regulator in Active power mode successful.
- kStatus_SPC_Busy – The SPC instance is busy to execute any type of power mode transition.
- kStatus_SPC_BandgapModeWrong – The bandgap is not enabled before invoking this function.
- kStatus_SPC_SYSLDOOverDriveVoltageFail – HVD of System VDD is not disable before setting to Over Drive voltage.
- kStatus_SPC_SYSLDOLowDriveStrengthIgnore – Set System LDO VDD regulator's driver strength to Low will be ignored.

status_t SPC_SetActiveModeSystemLDORegulatorVoltageLevel(SPC_Type *base, *spc_sys_ldo_voltage_level_t* voltageLevel)

Set System LDO Regulator voltage level in Active mode.

Note: The system LDO regulator can only operate at the overdrive voltage level for a limited amount of time for the life of chip.

Parameters

- base – SPC peripheral base address.
- voltageLevel – Specify the voltage level of System LDO Regulator in Active mode.

Return values

- kStatus_Success – Set System LDO Regulator voltage level in Active mode successfully.
- kStatus_SPC_SYSLDOOverDriveVoltageFail – Must disable system LDO high voltage detector before specifing overdrive voltage.

static inline *spc_sys_ldo_voltage_level_t* SPC_GetActiveModeSystemLDORegulatorVoltageLevel(SPC_Type *base)

Get System LDO Regulator voltage level in Active mode.

Parameters

- base – SPC peripheral base address.

Returns

System LDO Regulator voltage level in Active mode, please refer to *spc_sys_ldo_voltage_level_t*.

status_t SPC_SetActiveModeSystemLDORegulatorDriveStrength(SPC_Type *base, *spc_sys_ldo_drive_strength_t* driveStrength)

Set System LDO Regulator Drive Strength in Active mode.

Parameters

- base – SPC peripheral base address.
- driveStrength – Specify the drive strength of System LDO Regulator in Active mode.

Return values

- kStatus_Success – Set System LDO Regulator drive strength in Active mode successfully.
- kStatus_SPC_SYSLDOLowDriveStrengthIgnore – Attempt to specify low drive strength is ignored due to any voltage detect feature is enabled in active mode.
- kStatus_SPC_BandgapModeWrong – Bandgap mode in Active mode must be programmed to a value that enables the bandgap if attempt to specify normal drive strength.

static inline *spc_sys_ldo_drive_strength_t* SPC_GetActiveModeSystemLDORegulatorDriveStrength(SPC_Type *base)

Get System LDO Regulator Drive Strength in Active mode.

Parameters

- base – SPC peripheral base address.

Returns

System LDO regulator drive strength in Active mode, please refer to *spc_sys_ldo_drive_strength_t*.

status_t SPC_SetLowPowerModeSystemLDORegulatorConfig(SPC_Type *base, const *spc_lowpower_mode_sys_ldo_option_t* *option)

Configs System LDO regulator in low power modes.

This function configs System LDO regulator in low power modes. If System LDO VDD Regulator Drive strength is set to normal, bandgap mode in low power mode must be programmed to a value that enables the Bandgap. If any High voltage detectors or Low Voltage detectors are kept enabled, configuration to set System LDO Regulator drive strength as Low will be ignored.

Parameters

- base – SPC peripheral base address.
- option – Pointer to spc_lowpower_mode_sys_ldo_option_t structure.

Return values

- kStatus_Success – Config System LDO regulator in Low Power Mode successfully.
- kStatus_SPC_Busy – The SPC instance is busy to execute any type of power mode transition.
- kStatus_SPC_SYSLDOLowDriveStrengthIgnore – Set driver strength to low will be ignored.

status_t SPC_SetLowPowerModeSystemLDORegulatorDriveStrength(SPC_Type *base, *spc_sys_ldo_drive_strength_t* driveStrength)

Set System LDO Regulator drive strength in Low Power Mode.

Parameters

- base – SPC peripheral base address.
- driveStrength – Specify the drive strength of System LDO Regulator in Low Power Mode.

Return values

- kStatus_Success – Set System LDO Regulator drive strength in Low Power Mode successfully.
- kStatus_SPC_SYSLDOLowDriveStrengthIgnore – Attempt to specify low drive strength is ignored due to any voltage detect feature is enabled in low power mode.
- kStatus_SPC_BandgapModeWrong – Bandgap mode in low power mode must be programmed to a value that enables the bandgap if attempt to specify normal drive strength.

static inline *spc_sys_ldo_drive_strength_t* SPC_GetLowPowerModeSystemLDORegulatorDriveStrength(SPC_Type *base)

Get System LDO Regulator drive strength in Low Power Mode.

Parameters

- base – SPC peripheral base address.

Returns

System LDO regulator drive strength in Low Power Mode, please refer to *spc_sys_ldo_drive_strength_t*.

static inline void SPC_EnableDCDCRegulator(SPC_Type *base, bool enable)

Enable/Disable DCDC Regulator.

Note: The DCDC enable bit is write-once, settings only reset after a POR, LVD, or HVD event.

Parameters

- base – SPC peripheral base address.
- enable – Enable/Disable DCDC Regulator. true - Enable DCDC Regulator. false - Disable DCDC Regulator.

void SPC_SetDCDCBurstConfig(SPC_Type *base, *spc_dcdc_burst_config_t* *config)

Config DCDC Burst options.

Parameters

- base – SPC peripheral base address.
- config – Pointer to spc_dcdc_burst_config_t structure.

static inline void SPC_TriggerDCDCBurstRequest(SPC_Type *base)

Trigger a software burst request to DCDC.

Parameters

- base – SPC peripheral base address.

static inline bool SPC_CheckDCDCBurstAck(SPC_Type *base)

Check if burst acknowlege flag is asserted.

Parameters

- base – SPC peripheral base address.

Return values

- false – DCDC burst not complete.
- true – DCDC burst complete.

static inline void SPC_ClearDCDCBurstAckFlag(SPC_Type *base)

Clear DCDC busrt acknowledge flag.

Parameters

- base – SPC periphral base address.

void SPC_SetDCDCRefreshCount(SPC_Type *base, uint16_t count)

Set the count value of the reference clock to configure the period of DCDC not active.

Note: This function is only useful when DCDC's drive strength is set as pulse refresh.

Note: The pulse duration(time between on and off) is: reference clock period * (count + 2).

Parameters

- base – SPC peripheral base address.
- count – The count value, 16 bit width.

static inline void SPC_EnableDCDCBleedResistor(SPC_Type *base, bool enable)

Enable a bleed resistor to discharge DCDC output when DCDC is disabled.

Parameters

- base – SPC peripheral base address.
- enable – Used to enable/disable bleed resistor.

status_t SPC_SetActiveModeDCDCRegulatorConfig(SPC_Type *base, const *spc_active_mode_dcdc_option_t* *option)

Configs DCDC_CORE Regulator in Active mode.

Note: When changing the DCDC output voltage level, take care to change the CORE LDO voltage level.

Parameters

- base – SPC peripheral base address.
- option – Pointer to the spc_active_mode_dcdc_option_t structure.

Return values

- kStatus_Success – Config DCDC regulator in Active power mode successful.
- kStatus_SPC_Busy – The SPC instance is busy to execute any type of power mode transition.
- kStatus_SPC_BandgapModeWrong – Set DCDC_CORE Regulator drive strength to Normal, the Bandgap must be enabled.

static inline void SPC_SetActiveModeDCDCRegulatorVoltageLevel(SPC_Type *base, *spc_dcdc_voltage_level_t* voltageLevel)

Set DCDC_CORE Regulator voltage level in Active mode.

Note: When changing the DCDC output voltage level, take care to change the CORE LDO voltage level.

Parameters

- base – SPC peripheral base address.
- voltageLevel – Specify the DCDC_CORE Regulator voltage level, please refer to *spc_dcdc_voltage_level_t*.

static inline *spc_dcdc_voltage_level_t* SPC_GetActiveModeDCDCRegulatorVoltageLevel(SPC_Type *base)

Get DCDC_CORE Regulator voltage level in Active mode.

Parameters

- base – SPC peripheral base address.

Returns

DCDC_CORE Regulator voltage level, please refer to *spc_dcdc_voltage_level_t*.

status_t SPC_SetActiveModeDCDCRegulatorDriveStrength(SPC_Type *base, *spc_dcdc_drive_strength_t* driveStrength)

Set DCDC_CORE Regulator drive strength in Active mode.

Note: To set DCDC drive strength as Normal, the bandgap must be enabled.

Parameters

- base – SPC peripheral base address.
- driveStrength – Specify the DCDC_CORE regulator drive strength, please refer to *spc_dcdc_drive_strength_t*.

Return values

- kStatus_Success – Set DCDC_CORE Regulator drive strength in Active mode successfully.
- kStatus_SPC_BandgapModeWrong – Set DCDC_CORE Regulator drive strength to Normal, the Bandgap must be enabled.

static inline *spc_dcdc_drive_strength_t* SPC_GetActiveModeDCDCRegulatorDriveStrength(SPC_Type *base)

Get DCDC_CORE Regulator drive strength in Active mode.

Parameters

- base – SPC peripheral base address.

Returns

DCDC_CORE Regulator drive strength, please refer to *spc_dcdc_drive_strength_t*.

status_t SPC_SetLowPowerModeDCDCRegulatorConfig(SPC_Type *base, const *spc_lowpower_mode_dcdc_option_t* *option)

Configs DCDC_CORE Regulator in Low power modes.

Note: If DCDC_CORE Drive Strength is set to Normal, the Bandgap mode in Low Power mode must be programmed to a value that enables the Bandgap.

Note: In Deep Power Down mode, DCDC regulator is always turned off.

Parameters

- base – SPC peripheral base address.
- option – Pointer to the spc_lowpower_mode_dcdc_option_t structure.

Return values

- kStatus_Success – Config DCDC regulator in low power mode successfully.
- kStatus_SPC_Busy – The SPC instance is busy to execute any type of power mode transition.
- kStatus_SPC_BandgapModeWrong – The bandgap mode setting in Low Power mode is wrong.

status_t SPC_SetLowPowerModeDCDCRegulatorDriveStrength(SPC_Type *base, *spc_dcdc_drive_strength_t* driveStrength)

Set DCDC_CORE Regulator drive strength in Low power mode.

Note: To set drive strength as normal, the bandgap must be enabled.

Parameters

- base – SPC peripheral base address.
- driveStrength – Specify the DCDC_CORE Regulator drive strength, please refer to *spc_dcdc_drive_strength_t*.

Return values

- kStatus_Success – Set DCDC_CORE Regulator drive strength in Low power mode successfully.
- kStatus_SPC_BandgapModeWrong – Set DCDC_CORE Regulator drive strength to Normal, the Bandgap must be enabled.

static inline *spc_dcdc_drive_strength_t* SPC_GetLowPowerModeDCDCRegulatorDriveStrength(SPC_Type *base)

Get DCDC_CORE Regulator drive strength in Low power mode.

Parameters

- base – SPC peripheral base address.

Returns

DCDC_CORE Regulator drive strength, please refer to *spc_dcdc_drive_strength_t*.

static inline void SPC_SetLowPowerModeDCDCRegulatorVoltageLevel(SPC_Type *base, *spc_dcdc_voltage_level_t* voltageLevel)

Set DCDC_CORE Regulator voltage level in Low power mode.

a. Configure ACTIVE_CFG[DCDC_VDD_LVL] to same level programmed in #1.

Note: To change DCDC level in Low-Power mode:

a. Configure LP_CFG[DCDC_VDD_LVL] to desired level;

b. Configure LP_CFG[DCDC_VDD_DS] to low driver strength;

Note: After invoking this function, the voltage level in active mode(wakeup from low power modes) also changed, if it is necessary, please invoke *SPC_SetActiveModeDCDCRegulatorVoltageLevel()* to change to desried voltage level.

Parameters

- base – SPC peripheral base address.
- voltageLevel – Specify the DCDC_CORE Regulator voltage level, please refer to *spc_dcdc_voltage_level_t*.

static inline *spc_dcdc_voltage_level_t* SPC_GetLowPowerModeDCDCRegulatorVoltageLevel(SPC_Type *base)

Get DCDC_CORE Regulator voltage level in Low power mode.

Parameters

- base – SPC peripheral base address.

Returns

DCDC_CORE Regulator voltage level, please refer to *spc_dcdc_voltage_level_t*.

FSL_SPC_DRIVER_VERSION

SPC driver version 2.12.1.

SPC status enumeration.

Note: Some device(such as MCXA family) do not equip DCDC or System LDO, please refer to the reference manual to check.

Values:

enumerator kStatus_SPC_Busy

The SPC instance is busy executing any type of power mode transition.

enumerator kStatus_SPC_DCDCLowDriveStrengthIgnore

DCDC Low drive strength setting be ignored for LVD/HVD enabled.

enumerator kStatus_SPC_DCDCPulseRefreshModeIgnore

DCDC Pulse Refresh Mode drive strength setting be ignored for LVD/HVD enabled.

enumerator kStatus_SPC_SYSLDOOverDriveVoltageFail

SYS LDO regulate to Over drive voltage failed for SYS LDO HVD must be disabled.

enumerator kStatus_SPC_SYSLDOLowDriveStrengthIgnore

SYS LDO Low driver strength setting be ignored for LDO LVD/HVD enabled.

enumerator kStatus_SPC_CORELDOLowDriveStrengthIgnore

CORE LDO Low driver strength setting be ignored for LDO LVD/HVD enabled.

enumerator kStatus_SPC_BandgapModeWrong

Selected Bandgap Mode wrong.

enumerator kStatus_SPC_CORELDOVoltageWrong

Core LDO voltage is wrong.

enumerator kStatus_SPC_CORELDOVoltageSetFail

Core LDO voltage set fail.

enumerator kStatus_SPC_CORELDOVoltageDetectWrong

Settings of CORE_LDO voltage detection is not allowed.

enumerator kStatus_SPC_DCDCCoreLdoVoltageMisMatch
Target voltage level of DCDC not equal to CORE_LDO.

enum _spc_voltage_detect_flags
Voltage Detect Status Flags.
Values:

enumerator kSPC_IOVDDHighVoltageDetectFlag
IO VDD High-Voltage detect flag.

enumerator kSPC_IOVDDLowVoltageDetectFlag
IO VDD Low-Voltage detect flag.

enumerator kSPC_SystemVDDHighVoltageDetectFlag
System VDD High-Voltage detect flag.

enumerator kSPC_SystemVDDLowVoltageDetectFlag
System VDD Low-Voltage detect flag.

enumerator kSPC_CoreVDDHighVoltageDetectFlag
Core VDD High-Voltage detect flag.

enumerator kSPC_CoreVDDLowVoltageDetectFlag
Core VDD Low-Voltage detect flag.

enum _spc_power_domains
SPC power domain isolation status.

Note: Some devices(such as MCXA family) do not contain WAKE Power Domain, please refer to the reference manual to check.

Values:

enumerator kSPC_MAINPowerDomainRetain
Peripherals and IO pads retain in MAIN Power Domain.

enumerator kSPC_WAKEPowerDomainRetain
Peripherals and IO pads retain in WAKE Power Domain.

enum _spc_analog_module_control
The enumeration of all analog module that can be controlled by SPC in active or low-power modes.

Note: Enumerations may not suitable for all devices, please check the specific device's RM for supported analog modules.

Values:

enumerator kSPC_controlVref
Enable/disable VREF in active or low-power modes.

enumerator kSPC_controlUsb3vDet
Enable/disable USB3V_Det in active or low-power modes.

enumerator kSPC_controlVbat
Enable/disable VBAT in active or low-power modes.

enumerator kSPC_controlDac0
Enable/disable DAC0 in active or low-power modes.

enumerator kSPC_controlDac1
Enable/disable DAC1 in active or low-power modes.

enumerator kSPC_controlDac2
Enable/disable DAC2 in active or low-power modes.

enumerator kSPC_controlOpamp0
Enable/disable OPAMP0 in active or low-power modes.

enumerator kSPC_controlOpamp1
Enable/disable OPAMP1 in active or low-power modes.

enumerator kSPC_controlOpamp2
Enable/disable OPAMP2 in active or low-power modes.

enumerator kSPC_controlOpamp3
Enable/disable OPAMP3 in active or low-power modes.

enumerator kSPC_controlTsi0
Enable/disable TSI0 in active or low-power modes.

enumerator kSPC_controlCmp0
Enable/disable CMP0 in active or low-power modes.

enumerator kSPC_controlCmp1
Enable/disable CMP1 in active or low-power modes.

enumerator kSPC_controlCmp2
Enable/disable CMP2 in active or low-power modes.

enumerator kSPC_controlCmp0Dac
Enable/disable CMP0_DAC in active or low-power modes.

enumerator kSPC_controlCmp1Dac
Enable/disable CMP1_DAC in active or low-power modes.

enumerator kSPC_controlCmp2Dac

Enable/disable CMP2_DAC in active or low-power modes.

enumerator kSPC_controlAllModules

Enable/disable all modules in active or low-power modes.

enum _spc_power_domain_id

The enumeration of spc power domain, the connected power domain is chip specfic, please refer to chip's RM for details.

Values:

enumerator kSPC_PowerDomain0

Power domain0, the connected power domain is chip specific.

enumerator kSPC_PowerDomain1

Power domain1, the connected power domain is chip specific.

enum _spc_power_domain_low_power_mode

The enumeration of Power domain's low power mode.

Values:

enumerator kSPC_SleepWithSYSClockRunning

Power domain request SLEEP mode with SYS clock running.

enumerator kSPC_DeepSleepWithSysClockOff

Power domain request deep sleep mode with system clock off.

enumerator kSPC_PowerDownWithSysClockOff

Power domain request power down mode with system clock off.

enumerator kSPC_DeepPowerDownWithSysClockOff

Power domain request deep power down mode with system clock off.

enum _spc_lowPower_request_pin_polarity

SPC low power request output pin polarity.

Values:

enumerator kSPC_HighTruePolarity

Control the High Polarity of the Low Power Reqest Pin.

enumerator kSPC_LowTruePolarity

Control the Low Polarity of the Low Power Reqest Pin.

enum _spc_lowPower_request_output_override

SPC low power request output override.

Values:

enumerator kSPC_LowPowerRequestNotForced
Not Forced.

enumerator kSPC_LowPowerRequestReserved
Reserved.

enumerator kSPC_LowPowerRequestForcedLow
Forced Low (Ignore LowPower request output polarity setting.)

enumerator kSPC_LowPowerRequestForcedHigh
Forced High (Ignore LowPower request output polarity setting.)

enum _spc_bandgap_mode
SPC Bandgap mode enumeration in Active mode or Low Power mode.

Values:

enumerator kSPC_BandgapDisabled
Bandgap disabled.

enumerator kSPC_BandgapEnabledBufferDisabled
Bandgap enabled with Buffer disabled.

enumerator kSPC_BandgapEnabledBufferEnabled
Bandgap enabled with Buffer enabled.

enumerator kSPC_BandgapReserved
Reserved.

enum _spc_dcdc_voltage_level
DCDC regulator voltage level enumeration in Active mode or Low Power Mode.

Note: *kSPC_DCDC_RetentionVoltage* not supported for all power modes.

Values:

enumerator kSPC_DCDC_RetentionVoltage
DCDC_CORE Regulator regulate to retention Voltage(Only supportedin low power modes)

enumerator kSPC_DCDC_MidVoltage
DCDC_CORE Regulator regulate to Mid Voltage(1.0V).

enumerator kSPC_DCDC_NormalVoltage
DCDC_CORE Regulator regulate to Normal Voltage(1.1V).

enumerator kSPC_DCDC_OverdriveVoltage
DCDC_CORE Regulator regulate to Safe-Mode Voltage(1.2V).

enum _spc_dcdc_drive_strength

DCDC regulator Drive Strength enumeration in Active mode or Low Power Mode.

Note: Different drive strength differ in these DCDC characterstics: Maximum load current Quiescent current Transient response.

Values:

enumerator kSPC_DCDC_PulseRefreshMode

DCDC_CORE Regulator Drive Strength set to Pulse Refresh Mode, This enum member is only useful for Low Power Mode config, please note that pluse refresh mode is invalid in SLEEP mode.

enumerator kSPC_DCDC_LowDriveStrength

DCDC_CORE regulator Drive Strength set to low.

enumerator kSPC_DCDC_NormalDriveStrength

DCDC_CORE regulator Drive Strength set to Normal.

enum _spc_sys_ldo_voltage_level

SYS LDO regulator voltage level enumeration in Active mode.

Values:

enumerator kSPC_SysLDO_NormalVoltage

SYS LDO VDD Regulator regulate to Normal Voltage(1.8V).

enumerator kSPC_SysLDO_OverDriveVoltage

SYS LDO VDD Regulator regulate to Over Drive Voltage(2.5V).

enum _spc_sys_ldo_drive_strength

SYS LDO regulator Drive Strength enumeration in Active mode or Low Power mode.

Values:

enumerator kSPC_SysLDO_LowDriveStrength

SYS LDO VDD regulator Drive Strength set to low.

enumerator kSPC_SysLDO_NormalDriveStrength

SYS LDO VDD regulator Drive Strength set to Normal.

enum _spc_core_ldo_voltage_level

Core LDO regulator voltage level enumeration in Active mode or Low Power mode.

Values:

enumerator kSPC_CoreLDO_UnderDriveVoltage

Deprecated:

, to align with description of latest RM, please use *kSPC_Core_LDO_RetentionVoltage* as instead.

enumerator kSPC_Core_LDO_RetentionVoltage

Core LDO VDD regulator regulate to retention voltage, please note that only useful in low power modes and not all devices support this options please refer to devices' RM for details.

enumerator kSPC_CoreLDO_MidDriveVoltage

Core LDO VDD regulator regulate to Mid Drive Voltage.

enumerator kSPC_CoreLDO_NormalVoltage

Core LDO VDD regulator regulate to Normal Voltage.

enumerator kSPC_CoreLDO_OverDriveVoltage

Core LDO VDD regulator regulate to overdrive Voltage.

enum _spc_core_ldo_drive_strength

CORE LDO VDD regulator Drive Strength enumeration in Low Power mode.

Values:

enumerator kSPC_CoreLDO_LowDriveStrength

Core LDO VDD regulator Drive Strength set to low.

enumerator kSPC_CoreLDO_NormalDriveStrength

Core LDO VDD regulator Drive Strength set to Normal.

enum _spc_low_voltage_level_select

IO VDD Low-Voltage Level Select.

Values:

enumerator kSPC_LowVoltageNormalLevel

Deprecated:

, please use kSPC_LowVoltageHighRange as instead.

enumerator kSPC_LowVoltageSafeLevel

Deprecated:

, please use kSPC_LowVoltageLowRange as instead.

enumerator kSPC_LowVoltageHighRange

High range LVD threshold.

enumerator kSPC_LowVoltageLowRange

Low range LVD threshold.

enum _spc_sram_operate_voltage

The list of the operating voltage for the SRAM's read/write timing margin.

Values:

enumerator kSPC_sramOperateAt1P0V
SRAM configured for 1.0V operation.

enumerator kSPC_sramOperateAt1P1V
SRAM configured for 1.1V operation.

enumerator kSPC_sramOperateAt1P2V
SRAM configured for 1.2V operation.

typedef enum *_spc_power_domain_id* spc_power_domain_id_t
The enumeration of spc power domain, the connected power domain is chip specfic, please refer to chip's RM for details.

typedef enum *_spc_power_domain_low_power_mode* spc_power_domain_low_power_mode_t
The enumeration of Power domain's low power mode.

typedef enum *_spc_lowPower_request_pin_polarity* spc_lowpower_request_pin_polarity_t
SPC low power request output pin polarity.

typedef enum *_spc_lowPower_request_output_override* spc_lowpower_request_output_override_t
SPC low power request output override.

typedef enum *_spc_bandgap_mode* spc_bandgap_mode_t
SPC Bandgap mode enumeration in Active mode or Low Power mode.

typedef enum *_spc_dcdc_voltage_level* spc_dcdc_voltage_level_t
DCDC regulator voltage level enumeration in Active mode or Low Power Mode.

Note: *kSPC_DCDC_RetentionVoltage* not supported for all power modes.

typedef enum *_spc_dcdc_drive_strength* spc_dcdc_drive_strength_t
DCDC regulator Drive Strength enumeration in Active mode or Low Power Mode.

Note: Different drive strength differ in these DCDC characterstics: Maximum load current Quiescent current Transient response.

typedef enum *_spc_sys_ldo_voltage_level* spc_sys_ldo_voltage_level_t
SYS LDO regulator voltage level enumeration in Active mode.

typedef enum *_spc_sys_ldo_drive_strength* spc_sys_ldo_drive_strength_t
SYS LDO regulator Drive Strength enumeration in Active mode or Low Power mode.

typedef enum *_spc_core_ldo_voltage_level* spc_core_ldo_voltage_level_t
Core LDO regulator voltage level enumeration in Active mode or Low Power mode.

typedef enum *_spc_core_ldo_drive_strength* spc_core_ldo_drive_strength_t
CORE LDO VDD regulator Drive Strength enumeration in Low Power mode.

typedef enum *_spc_low_voltage_level_select* spc_low_voltage_level_select_t
IO VDD Low-Voltage Level Select.

typedef enum *_spc_sram_operate_voltage* spc_sram_operate_voltage_t
The list of the operating voltage for the SRAM's read/write timing margin.

typedef struct *_spc_sram_voltage_config* spc_sram_voltage_config_t

typedef struct *_spc_lowpower_request_config* spc_lowpower_request_config_t
Low Power Request output pin configuration.

typedef struct *_spc_active_mode_core_ldo_option* spc_active_mode_core_ldo_option_t
Core LDO regulator options in Active mode.

typedef struct *_spc_active_mode_sys_ldo_option* spc_active_mode_sys_ldo_option_t
System LDO regulator options in Active mode.

typedef struct *_spc_active_mode_dcdc_option* spc_active_mode_dcdc_option_t
DCDC regulator options in Active mode.

typedef struct *_spc_lowpower_mode_core_ldo_option* spc_lowpower_mode_core_ldo_option_t
Core LDO regulator options in Low Power mode.

typedef struct *_spc_lowpower_mode_sys_ldo_option* spc_lowpower_mode_sys_ldo_option_t
System LDO regulator options in Low Power mode.

typedef struct *_spc_lowpower_mode_dcdc_option* spc_lowpower_mode_dcdc_option_t
DCDC regulator options in Low Power mode.

typedef struct *_spc_dcdc_burst_config* spc_dcdc_burst_config_t
DCDC Burst configuration.

Deprecated:
Do not recommend to use this structure.

typedef struct *_spc_voltage_detect_option* spc_voltage_detect_option_t
CORE/SYS/IO VDD Voltage Detect options.

typedef struct *_spc_core_voltage_detect_config* spc_core_voltage_detect_config_t
Core Voltage Detect configuration.

typedef struct *_spc_system_voltage_detect_config* spc_system_voltage_detect_config_t
System Voltage Detect Configuration.

typedef struct *_spc_io_voltage_detect_config* spc_io_voltage_detect_config_t
IO Voltage Detect Configuration.

typedef struct *_spc_active_mode_regulators_config* spc_active_mode_regulators_config_t
Active mode configuration.

typedef struct *_spc_lowpower_mode_regulators_config* spc_lowpower_mode_regulators_config_t
Low Power Mode configuration.

SPC_EVD_CFG_REG_EVDISO_SHIFT

SPC_EVD_CFG_REG_EVDLPISO_SHIFT

SPC_EVD_CFG_REG_EVDSTAT_SHIFT

SPC_EVD_CFG_REG_EVDISO(x)

SPC_EVD_CFG_REG_EVDLPISO(x)

SPC_EVD_CFG_REG_EVDSTAT(x)

struct _spc_sram_voltage_config
#include <fsl_spc.h>

Public Members

spc_sram_operate_voltage_t operateVoltage
Specifies the operating voltage for the SRAM's read/write timing margin.

bool requestVoltageUpdate
Used to control whether request an SRAM trim value change.

struct _spc_lowpower_request_config
#include <fsl_spc.h> Low Power Request output pin configuration.

Public Members

bool enable
Low Power Request Output enable.

spc_lowpower_request_pin_polarity_t polarity
Low Power Request Output pin polarity select.

spc_lowpower_request_output_override_t override
Low Power Request Output Override.

struct _spc_active_mode_core_ldo_option
#include <fsl_spc.h> Core LDO regulator options in Active mode.

Public Members

spc_core_ldo_voltage_level_t CoreLDOVoltage
Core LDO Regulator Voltage Level selection in Active mode.

spc_core_ldo_drive_strength_t CoreLDODriveStrength
Core LDO Regulator Drive Strength selection in Active mode

struct _spc_active_mode_sys_ldo_option
#include <fsl_spc.h> System LDO regulator options in Active mode.

Public Members

spc_sys_ldo_voltage_level_t SysLDOVoltage
System LDO Regulator Voltage Level selection in Active mode.

spc_sys_ldo_drive_strength_t SysLDODriveStrength
System LDO Regulator Drive Strength selection in Active mode.

struct _spc_active_mode_dcdc_option
#include <fsl_spc.h> DCDC regulator options in Active mode.

Public Members

spc_dcdc_voltage_level_t DCDCVoltage
DCDC Regulator Voltage Level selection in Active mode.

spc_dcdc_drive_strength_t DCDCDriveStrength
DCDC_CORE Regulator Drive Strength selection in Active mode.

struct _spc_lowpower_mode_core_ldo_option
#include <fsl_spc.h> Core LDO regulator options in Low Power mode.

Public Members

spc_core_ldo_voltage_level_t CoreLDOVoltage
Core LDO Regulator Voltage Level selection in Low Power mode.

spc_core_ldo_drive_strength_t CoreLDODriveStrength
Core LDO Regulator Drive Strength selection in Low Power mode

struct _spc_lowpower_mode_sys_ldo_option
#include <fsl_spc.h> System LDO regulator options in Low Power mode.

Public Members

spc_sys_ldo_drive_strength_t SysLDODriveStrength
System LDO Regulator Drive Strength selection in Low Power mode.

struct _spc_lowpower_mode_dcdc_option
#include <fsl_spc.h> DCDC regulator options in Low Power mode.

Public Members

spc_dcdc_voltage_level_t DCDCVoltage
DCDC Regulator Voltage Level selection in Low Power mode.

spc_dcdc_drive_strength_t DCDCDriveStrength
DCDC_CORE Regulator Drive Strength selection in Low Power mode.

struct _spc_dcdc_burst_config
#include <fsl_spc.h> DCDC Burst configuration.

Deprecated:
Do not recommend to use this structure.

Public Members

bool sofwareBurstRequest
Enable/Disable DCDC Software Burst Request.

bool externalBurstRequest
Enable/Disable DCDC External Burst Request.

bool stabilizeBurstFreq
Enable/Disable DCDC frequency stabilization.

uint8_t freq
The frequency of the current burst.

struct _spc_voltage_detect_option
#include <fsl_spc.h> CORE/SYS/IO VDD Voltage Detect options.

Public Members

bool HVDInterruptEnable
CORE/SYS/IO VDD High Voltage Detect interrupt enable.

bool HVDResetEnable
CORE/SYS/IO VDD High Voltage Detect reset enable.

bool LVDInterruptEnable
CORE/SYS/IO VDD Low Voltage Detect interrupt enable.

bool LVDResetEnable
CORE/SYS/IO VDD Low Voltage Detect reset enable.

struct _spc_core_voltage_detect_config
#include <fsl_spc.h> Core Voltage Detect configuration.

Public Members

spc_voltage_detect_option_t option
Core VDD Voltage Detect option.

struct _spc_system_voltage_detect_config
#include <fsl_spc.h> System Voltage Detect Configuration.

Public Members

spc_voltage_detect_option_t option
System VDD Voltage Detect option.

spc_low_voltage_level_select_t level
Deprecated:
, reserved for all devices, will removed in next release.

struct _spc_io_voltage_detect_config
#include <fsl_spc.h> IO Voltage Detect Configuration.

Public Members

spc_voltage_detect_option_t option
IO VDD Voltage Detect option.

spc_low_voltage_level_select_t level
IO VDD Low-voltage level selection.

struct _spc_active_mode_regulators_config
#include <fsl_spc.h> Active mode configuration.

Public Members

spc_bandgap_mode_t bandgapMode
Specify bandgap mode in active mode.

bool lpBuff
Enable/disable CMP bandgap buffer.

spc_active_mode_dcdc_option_t DCDCOption
Specify DCDC configurations in active mode.

spc_active_mode_sys_ldo_option_t SysLDOOption
Specify System LDO configurations in active mode.

spc_active_mode_core_ldo_option_t CoreLDOOption
Specify Core LDO configurations in active mode.

struct _spc_lowpower_mode_regulators_config
#include <fsl_spc.h> Low Power Mode configuration.

Public Members

bool lpIREF
Enable/disable low power IREF in low power modes.

spc_bandgap_mode_t bandgapMode
Specify bandgap mode in low power modes.

bool lpBuff
Enable/disable CMP bandgap buffer in low power modes.

bool CoreIVS
Enable/disable CORE VDD internal voltage scaling.

spc_lowpower_mode_dcdc_option_t DCDCOption
Specify DCDC configurations in low power modes.

spc_lowpower_mode_sys_ldo_option_t SysLDOOption
Specify system LDO configurations in low power modes.

spc_lowpower_mode_core_ldo_option_t CoreLDOOption
Specify core LDO configurations in low power modes.

2.63 MCX_VBAT: Smart Power Switch

The enumeration of VBAT module status.

Values:

enumerator kStatus_VBAT_Fro16kNotEnabled
Internal 16kHz free running oscillator not enabled.

enumerator kStatus_VBAT_BandgapNotEnabled
Bandgap not enabled.

enumerator kStatus_VBAT_WrongCapacitanceValue
Wrong capacitance for selected oscillator mode.

enumerator kStatus_VBAT_ClockMonitorLocked
Clock monitor locked.

enumerator kStatus_VBAT_OSC32KNotReady
OSC32K not ready.

enumerator kStatus_VBAT_LDONotReady
LDO not ready.

enumerator kStatus_VBAT_TamperLocked
Tamper locked.

enum _vbat_status_flag
The enumeration of VBAT status flags.

Values:

enumerator kVBAT_StatusFlagPORDetect
VBAT domain has been reset

enumerator kVBAT_StatusFlagWakeupPin
A falling edge is detected on the wakeup pin.

enumerator kVBAT_StatusFlagBandgapTimer0
Bandgap Timer0 period reached.

enumerator kVBAT_StatusFlagBandgapTimer1
Bandgap Timer1 period reached.

enumerator kVBAT_StatusFlagLdoReady
LDO is enabled and ready.

enumerator kVBAT_StatusFlagOsc32kReady
OSC32k is enabled and clock is ready.

enumerator kVBAT_StatusFlagInterrupt0Detect
Interrupt 0 asserted.

enumerator kVBAT_StatusFlagInterrupt1Detect
Interrupt 1 asserted.

enumerator kVBAT_StatusFlagInterrupt2Detect
Interrupt 2 asserted.

enumerator kVBAT_StatusFlagInterrupt3Detect
Interrupt 3 asserted.

enum _vbat_interrupt_enable
The enumeration of VBAT interrupt enable.

Values:

enumerator kVBAT_InterruptEnablePORDetect
Enable POR detect interrupt.

enumerator kVBAT_InterruptEnableWakeupPin
Enable the interrupt when a falling edge is detected on the wakeup pin.

enumerator kVBAT_InterruptEnableBandgapTimer0
Enable the interrupt if Bandgap Timer0 period reached.

enumerator kVBAT_InterruptEnableBandgapTimer1
Enable the interrupt if Bandgap Timer1 period reached.

enumerator kVBAT_InterruptEnableLdoReady
Enable LDO ready interrupt.

enumerator kVBAT_InterruptEnableOsc32kReady
Enable OSC32K ready interrupt.

enumerator kVBAT_InterruptEnableInterrupt0
Enable the interrupt0.

enumerator kVBAT_InterruptEnableInterrupt1
Enable the interrupt1.

enumerator kVBAT_InterruptEnableInterrupt2
Enable the interrupt2.

enumerator kVBAT_InterruptEnableInterrupt3
Enable the interrupt3.

enumerator kVBAT_AllInterruptsEnable
Enable all interrupts.

enum _vbat_wakeup_enable
The enumeration of VBAT wakeup enable.

Values:

enumerator kVBAT_WakeupEnablePORDetect
Enable POR detect wakeup.

enumerator kVBAT_WakeupEnableWakeupPin
Enable wakeup feature when a falling edge is detected on the wakeup pin.

enumerator kVBAT_WakeupEnableBandgapTimer0
Enable wakeup feature when bandgap timer0 period reached.

enumerator kVBAT_WakeupEnableBandgapTimer1
Enable wakeup feature when bandgap timer1 period reached.

enumerator kVBAT_WakeupEnableLdoReady
Enable wakeup when LDO ready.

enumerator kVBAT_WakeupEnableOsc32kReady
Enable wakeup when OSC32k ready.

enumerator kVBAT_WakeupEnableInterrupt0
Enable wakeup when interrupt0 asserted.

enumerator kVBAT_WakeupEnableInterrupt1
Enable wakeup when interrupt1 asserted.

enumerator kVBAT_WakeupEnableInterrupt2
Enable wakeup when interrupt2 asserted.

enumerator kVBAT_WakeupEnableInterrupt3
Enable wakeup when interrupt3 asserted.

enumerator kVBAT_AllWakeupsEnable
Enable all wakeup.

enum _vbat_tamper_enable
The enumeration of VBAT tamper enable.
Values:

enumerator kVBAT_TamperEnablePOR
Enable tamper if POR asserted in STATUS register.

enumerator kVBAT_TamperEnableClockDetect
Enable tamper if clock monitor detect an error.

enumerator kVBAT_TamperEnableConfigDetect
Enable tamper if configuration error detected.

enumerator kVBAT_TamperEnableVoltageDetect
Enable tamper if voltage monitor detect an error.

enumerator kVBAT_TamperEnableTemperatureDetect
Enable tamper if temperature monitor detect an error.

enumerator kVBAT_TamperEnableSec0Detect
Enable tamper if security input 0 detect an error.

enum _vbat_bandgap_timer_id
The enumeration of bandgap timer id, VBAT support two bandgap timers.

Values:

enumerator kVBAT_BandgapTimer0
Bandgap Timer0.

enumerator kVBAT_BandgapTimer1
Bandgap Timer1.

enum _vbat_clock_enable
The enumeration of connections for OSC32K/FRO32K output clock to other modules.

Values:

enumerator kVBAT_EnableClockToDomain0
Enable clock to power domain0.

enumerator kVBAT_EnableClockToDomain1
Enable clock to power domain1.

enumerator kVBAT_EnableClockToDomain2
Enable clock to power domain2.

enumerator kVBAT_EnableClockToDomain3
Enable clock to power domain3.

enum _vbat_ram_array
The enumeration of SRAM arrays that controlled by VBAT. .
Values:

enumerator kVBAT_SramArray0
Specify SRAM array0 that controlled by VBAT.

enumerator kVBAT_SramArray1
Specify SRAM array1 that controlled by VBAT.

enumerator kVBAT_SramArray2
Specify SRAM array2 that controlled by VBAT.

enumerator kVBAT_SramArray3
Specify SRAM array3 that controlled by VBAT.

enum _vbat_bandgap_refresh_period
The enumeration of bandgap refresh period.
Values:

enumerator kVBAT_BandgapRefresh7P8125ms
Bandgap refresh every 7.8125ms.

enumerator kVBAT_BandgapRefresh15P625ms
Bandgap refresh every 15.625ms.

enumerator kVBAT_BandgapRefresh31P25ms
Bandgap refresh every 31.25ms.

enumerator kVBAT_BandgapRefresh62P5ms
Bandgap refresh every 62.5ms.

enum _vbat_bandgap_timer0_timeout_period
The enumeration of bandgap timer0 timeout period.
Values:

enumerator kVBAT_BangapTimer0Timeout1s
Bandgap timer0 timerout every 1s.

enumerator kVBAT_BangapTimer0Timeout500ms
Bandgap timer0 timerout every 500ms.

enumerator kVBAT_BangapTimer0Timeout250ms
Bandgap timer0 timerout every 250ms.

enumerator kVBAT_BangapTimer0Timeout125ms
Bandgap timer0 timerout every 125ms.

enumerator kVBAT_BangapTimer0Timeout62P5ms
Bandgap timer0 timerout every 62.5ms.

enumerator kVBAT_BangapTimer0Timeout31P25ms

Bandgap timer0 timerout every 31.25ms.

enum _vbat_osc32k_operate_mode

The enumeration of osc32k operate mode, including Bypass mode, low power switched mode and so on.

Values:

enumerator kVBAT_Osc32kEnabledToTransconductanceMode

Set to transconductance mode.

enumerator kVBAT_Osc32kEnabledToLowPowerBackupMode

Set to low power backup mode.

enumerator kVBAT_Osc32kEnabledToLowPowerSwitchedMode

Set to low power switched mode.

enum _vbat_osc32k_load_capacitance_select

The enumeration of OSC32K load capacitance.

Values:

enumerator kVBAT_Osc32kCrystalLoadCap0pF

Internal capacitance bank is enabled, set the internal capacitance to 0 pF.

enumerator kVBAT_Osc32kCrystalLoadCap2pF

Internal capacitance bank is enabled, set the internal capacitance to 2 pF.

enumerator kVBAT_Osc32kCrystalLoadCap4pF

Internal capacitance bank is enabled, set the internal capacitance to 4 pF.

enumerator kVBAT_Osc32kCrystalLoadCap6pF

Internal capacitance bank is enabled, set the internal capacitance to 6 pF.

enumerator kVBAT_Osc32kCrystalLoadCap8pF

Internal capacitance bank is enabled, set the internal capacitance to 8 pF.

enumerator kVBAT_Osc32kCrystalLoadCap10pF

Internal capacitance bank is enabled, set the internal capacitance to 10 pF.

enumerator kVBAT_Osc32kCrystalLoadCap12pF

Internal capacitance bank is enabled, set the internal capacitance to 12 pF.

enumerator kVBAT_Osc32kCrystalLoadCap14pF

Internal capacitance bank is enabled, set the internal capacitance to 14 pF.

enumerator kVBAT_Osc32kCrystalLoadCap16pF

Internal capacitance bank is enabled, set the internal capacitance to 16 pF.

enumerator kVBAT_Osc32kCrystalLoadCap18pF
Internal capacitance bank is enabled, set the internal capacitance to 18 pF.

enumerator kVBAT_Osc32kCrystalLoadCap20pF
Internal capacitance bank is enabled, set the internal capacitance to 20 pF.

enumerator kVBAT_Osc32kCrystalLoadCap22pF
Internal capacitance bank is enabled, set the internal capacitance to 22 pF.

enumerator kVBAT_Osc32kCrystalLoadCap24pF
Internal capacitance bank is enabled, set the internal capacitance to 24 pF.

enumerator kVBAT_Osc32kCrystalLoadCap26pF
Internal capacitance bank is enabled, set the internal capacitance to 26 pF.

enumerator kVBAT_Osc32kCrystalLoadCap28pF
Internal capacitance bank is enabled, set the internal capacitance to 28 pF.

enumerator kVBAT_Osc32kCrystalLoadCap30pF
Internal capacitance bank is enabled, set the internal capacitance to 30 pF.

enumerator kVBAT_Osc32kCrystalLoadCapBankDisabled
Internal capacitance bank is disabled.

enum _vbat_osc32k_start_up_time
The enumeration of start-up time of the oscillator.
Values:

enumerator kVBAT_Osc32kStartUpTime8Sec
Configure the start-up time as 8 seconds.

enumerator kVBAT_Osc32kStartUpTime4Sec
Configure the start-up time as 4 seconds.

enumerator kVBAT_Osc32kStartUpTime2Sec
Configure the start-up time as 2 seconds.

enumerator kVBAT_Osc32kStartUpTime1Sec
Configure the start-up time as 1 seconds.

enumerator kVBAT_Osc32kStartUpTime0P5Sec
Configure the start-up time as 0.5 seconds.

enumerator kVBAT_Osc32kStartUpTime0P25Sec
Configure the start-up time as 0.25 seconds.

enumerator kVBAT_Osc32kStartUpTime0P125Sec
Configure the start-up time as 0.125 seconds.

enumerator kVBAT_Osc32kStartUpTime0P5MSec
Configure the start-up time as 0.5 milliseconds.

enum _vbat_internal_module_supply
The enumeration of VBAT module supplies.

Values:

enumerator kVBAT_ModuleSuppliedByVddBat
VDD_BAT supplies VBAT modules.

enumerator kVBAT_ModuleSuppliedByVddSys
VDD_SYS supplies VBAT modules.

enum _vbat_clock_monitor_divide_trim
The enumeration of VBAT clock monitor divide trim value.

Values:

enumerator kVBAT_ClockMonitorOperateAt1kHz
Clock monitor operates at 1 kHz.

enumerator kVBAT_ClockMonitorOperateAt64Hz
Clock monitor operates at 64 Hz.

enum _vbat_clock_monitor_freq_trim
The enumeration of VBAT clock monitor frequency trim value used to adjust the clock monitor assert.

Values:

enumerator kVBAT_ClockMonitorAssert2Cycle
Clock monitor assert 2 cycles after expected edge.

enumerator kVBAT_ClockMonitorAssert4Cycle
Clock monitor assert 4 cycles after expected edge.

enumerator kVBAT_ClockMonitorAssert6Cycle
Clock monitor assert 8 cycles after expected edge.

enumerator kVBAT_ClockMonitorAssert8Cycle
Clock monitor assert 8 cycles after expected edge.

typedef enum *_vbat_bandgap_refresh_period* vbat_bandgap_refresh_period_t
The enumeration of bandgap refresh period.

typedef enum *_vbat_bandgap_timer0_timeout_period* vbat_bandgap_timer0_timeout_period_t
The enumeration of bandgap timer0 timeout period.

typedef enum *_vbat_osc32k_operate_mode* vbat_osc32k_operate_mode_t
The enumeration of osc32k operate mode, including Bypass mode, low power switched mode and so on.

typedef enum *_vbat_osc32k_load_capacitance_select* vbat_osc32k_load_capacitance_select_t

The enumeration of OSC32K load capacitance.

typedef enum *_vbat_osc32k_start_up_time* vbat_osc32k_start_up_time_t

The enumeration of start-up time of the oscillator.

typedef enum *_vbat_internal_module_supply* vbat_internal_module_supply_t

The enumeration of VBAT module supplies.

typedef enum *_vbat_clock_monitor_divide_trim* vbat_clock_monitor_divide_trim_t

The enumeration of VBAT clock monitor divide trim value.

typedef enum *_vbat_clock_monitor_freq_trim* vbat_clock_monitor_freq_trim_t

The enumeration of VBAT clock monitor frequency trim value used to adjust the clock monitor assert.

typedef struct *_vbat_fro16k_config* vbat_fro16k_config_t

The structure of internal 16kHz free running oscillator attributes.

typedef struct *_vbat_clock_monitor_config* vbat_clock_monitor_config_t

The structure of internal clock monitor, including divide trim and frequency trim.

typedef struct *_vbat_tamper_config* vbat_tamper_config_t

The structure of Tamper configuration.

FSL_VBAT_DRIVER_VERSION

VBAT driver version 2.6.0.

VBAT_LDORAMC_RET_MASK

VBAT_LDORAMC_RET_SHIFT

VBAT_LDORAMC_RET(x)

kVBAT_EnableClockToVddBat

kVBAT_EnableClockToVddSys

kVBAT_EnableClockToVddWake

kVBAT_EnableClockToVddMain

void VBAT_ConfigFRO16k(VBAT_Type *base, const *vbat_fro16k_config_t* *config)

Configure internal 16kHz free running oscillator, including enabel FRO16k, gate FRO16k output.

Parameters

- base – VBAT peripheral base address.
- config – Pointer to *vbat_fro16k_config_t* structure.

static inline void VBAT_EnableFRO16k(VBAT_Type *base, bool enable)

Enable/disable internal 16kHz free running oscillator.

Parameters

- base – VBAT peripheral base address.
- enable – Used to enable/disable 16kHz FRO.
  - **true** Enable internal 16kHz free running oscillator.
  - **false** Disable internal 16kHz free running oscillator.

static inline bool VBAT_CheckFRO16kEnabled(VBAT_Type *base)

Check if internal 16kHz free running oscillator is enabled.

Parameters

- base – VBAT peripheral base address.

Return values

- true – The internal 16kHz Free running oscillator is enabled.
- false – The internal 16kHz Free running oscillator is enabled.

static inline void VBAT_UngateFRO16k(VBAT_Type *base, uint8_t connectionsMask)

Enable FRO16kHz output clock to selected modules.

Parameters

- base – VBAT peripheral base address.
- connectionsMask – The mask of modules that FRO16k is connected, should be the OR'ed value of *vbat_clock_enable_t*.

static inline void VBAT_GateFRO16k(VBAT_Type *base, uint8_t connectionsMask)

Disable FRO16kHz output clock to selected modules.

Parameters

- base – VBAT peripheral base address.
- connectionsMask – The OR'ed value of *vbat_clock_enable_t*.

static inline void VBAT_LockFRO16kSettings(VBAT_Type *base)

Lock settings of internal 16kHz free running oscillator, please note that if locked 16kHz FRO's settings can not be updated until the next POR.

Note: Please note that the operation to ungate/gate FRO 16kHz output clock can not be locked by this function.

Parameters

- base – VBAT peripheral base address.

static inline bool VBAT_CheckFRO16kSettingsLocked(VBAT_Type *base)

Check if FRO16K settings are locked.

Parameters

- base – VBAT peripheral base address.

Returns

true in case of FRO16k settings are locked, false in case of FRO16k settings are not locked.

static inline void VBAT_EnableCrystalOsc32k(VBAT_Type *base, bool enable)

Enable/disable 32K Crystal Oscillator.

Parameters

- base – VBAT peripheral base address.
- enable – Used to enable/disable 32k Crystal Oscillator:
  - **true** Enable crystal oscillator and polling status register to check clock is ready.
  - **false** Disable crystal oscillator.

static inline void VBAT_BypassCrystalOsc32k(VBAT_Type *base, bool enableBypass)

Bypass 32k crystal oscillator, the clock is still output by oscillator but this clock is the same as clock provided on EXTAL pin.

Note: In bypass mode, oscillator must be enabled; To exit bypass mode, oscillator must be disabled.

Parameters

- base – VBAT peripheral base address.
- enableBypass – Used to enter/exit bypass mode:
  - **true** Enter into bypass mode;
  - **false** Exit bypass mode.

static inline void VBAT_AdjustCrystalOsc32kAmplifierGain(VBAT_Type *base, uint8_t coarse, uint8_t fine)

Adjust 32k crystal oscillator amplifier gain.

Parameters

- base – VBAT peripheral base address.
- coarse – Specify amplifier coarse trim value.
- fine – Specify amplifier fine trim value.

status_t VBAT_SetCrystalOsc32kModeAndLoadCapacitance(VBAT_Type *base, *vbat_osc32k_operate_mode_t* operateMode, *vbat_osc32k_load_capacitance_select_t* xtalCap, *vbat_osc32k_load_capacitance_select_t* extalCap)

Set 32k crystal oscillator mode and load capacitance for the XTAL/EXTAL pin.

Parameters

- base – VBAT peripheral base address.
- operateMode – Specify the crystal oscillator mode, please refer to *vbat_osc32k_operate_mode_t*.
- xtalCap – Specify the internal capacitance for the XTAL pin from the capacitor bank.
- extalCap – Specify the internal capacitance for the EXTAL pin from the capacitor bank.

Return values

- kStatus_VBAT_WrongCapacitanceValue – The load capacitance value to set is not align with operate mode's requirements.
- kStatus_Success – Success to set operate mode and load capacitance.

static inline void VBAT_TrimCrystalOsc32kStartupTime(VBAT_Type *base, *vbat_osc32k_start_up_time_t* startupTime)

Trim 32k crystal oscillator startup time.

Parameters

- base – VBAT peripheral base address.
- startupTime – Specify the startup time of the oscillator.

static inline void VBAT_SetOsc32kSwitchModeComparatorTrimValue(VBAT_Type *base, uint8_t comparatorTrimValue)

Set crystal oscillator comparator trim value when oscillator is set as low power switch mode.

Parameters

- base – VBAT peripheral base address.
- comparatorTrimValue – Comparator trim value, ranges from 0 to 7.

static inline void VBAT_SetOsc32kSwitchModeDelayTrimValue(VBAT_Type *base, uint8_t delayTrimValue)

Set crystal oscillator delay trim value when oscillator is set as low power switch mode.

Parameters

- base – VBAT peripheral base address.
- delayTrimValue – Delay trim value, ranges from 0 to 15.

static inline void VBAT_SetOsc32kSwitchModeCapacitorTrimValue(VBAT_Type *base, uint8_t capacitorTrimValue)

Set crystal oscillator capacitor trim value when oscillator is set as low power switch mode.

Parameters

- base – VBAT peripheral base address.
- capacitorTrimValue – Capacitor value to trim, ranges from 0 to 3.

static inline void VBAT_LookOsc32kSettings(VBAT_Type *base)

Lock Osc32k settings, after locked all writes to the Oscillator registers are blocked.

Parameters

- base – VBAT peripheral base address.

static inline void VBAT_UnlockOsc32kSettings(VBAT_Type *base)

Unlock Osc32k settings.

Parameters

- base – VBAT peripheral base address.

static inline bool VBAT_CheckOsc32kSettingsLocked(VBAT_Type *base)

Check if osc32k settings are locked.

Parameters

- base – VBAT peripheral base address.

Returns

true in case of osc32k settings are locked, false in case of osc32k settings are not locked.

static inline void VBAT_UngateOsc32k(VBAT_Type *base, uint8_t connectionsMask)

Enable OSC32k output clock to selected modules.

Parameters

- base – VBAT peripheral base address.
- connectionsMask – The OR'ed value of *vbat_clock_enable_t*.

static inline void VBAT_GateOsc32k(VBAT_Type *base, uint8_t connectionsMask)

Disable OSC32k output clock to selected modules.

Parameters

- base – VBAT peripheral base address.
- connectionsMask – The OR'ed value of *vbat_clock_enable_t*.

status_t VBAT_EnableBandgap(VBAT_Type *base, bool enable)

Enable/disable Bandgap.

Note: The FRO16K must be enabled before enabling the bandgap.

Note: This setting can be locked by *VBAT_LockRamLdoSettings()* function.

Parameters

- base – VBAT peripheral base address.
- enable – Used to enable/disable bandgap.
  - **true** Enable the bandgap.
  - **false** Disable the bandgap.

Return values

- kStatus_Success – Success to enable/disable the bandgap.
- kStatus_VBAT_Fro16kNotEnabled – Fail to enable the bandgap due to FRO16k is not enabled previously.

static inline bool VBAT_CheckBandgapEnabled(VBAT_Type *base)

Check if bandgap is enabled.

Parameters

- base – VBAT peripheral base address.

Return values

- true – The bandgap is enabled.
- false – The bandgap is disabled.

static inline void VBAT_EnableBandgapRefreshMode(VBAT_Type *base, bool enableRefreshMode)

Enable/disable bandgap low power refresh mode.

Note: For lowest power consumption, refresh mode must be enabled.

Note: This setting can be locked by *VBAT_LockRamLdoSettings()* function.

Parameters

- base – VBAT peripheral base address.
- enableRefreshMode – Used to enable/disable bandgap low power refresh mode.
  - **true** Enable bandgap low power refresh mode.
  - **false** Disable bandgap low power refresh mode.

status_t VBAT_EnableBackupSRAMRegulator(VBAT_Type *base, bool enable)

Enable/disable Backup RAM Regulator(RAM_LDO).

Note: This setting can be locked by *VBAT_LockRamLdoSettings()* function.

Parameters

- base – VBAT peripheral base address.
- enable – Used to enable/disable RAM_LDO.
  - **true** Enable backup SRAM regulator.
  - **false** Disable backup SRAM regulator.

Return values

- kStatusSuccess – Success to enable/disable backup SRAM regulator.
- kStatus_VBAT_Fro16kNotEnabled – Fail to enable backup SRAM regulator due to FRO16k is not enabled previously.
- kStatus_VBAT_BandgapNotEnabled – Fail to enable backup SRAM regulator due to the bandgap is not enabled previously.

static inline void VBAT_LockRamLdoSettings(VBAT_Type *base)

Lock settings of RAM_LDO, please note that if locked then RAM_LDO's settings can not be updated until the next POR.

Parameters

- base – VBAT peripheral base address.

static inline bool VBAT_CheckRamLdoSettingsLocked(VBAT_Type *base)

Check if RAM_LDO settings is locked.

Parameters

- base – VBAT peripheral base address.

Returns

true in case of RAM_LDO settings are locked, false in case of RAM_LDO settings are unlocked.

status_t VBAT_SwitchSRAMPowerByLDOSRAM(VBAT_Type *base)

Switch the SRAM to be powered by LDO_RAM.

Note: This function can be used to switch the SRAM to the VBAT retention supply at any time, but please note that the SRAM must not be accessed during this time.

Note: Invoke this function to switch power supply before switching off external power.

Note: RAM_LDO must be enabled before invoking this function.

Note: To access the SRAM arrays retained by the LDO_RAM, please invoke *VBAT_SwitchSRAMPowerBySocSupply()*, after external power is switched back on.

Parameters

- base – VBAT peripheral base address.

Return values

- kStatusSuccess – Success to Switch SRAM powered by VBAT.
- kStatus_VBAT_Fro16kNotEnabled – Fail to switch SRAM powered by VBAT due to FRO16K not enabled previously.

static inline void VBAT_SwitchSRAMPowerBySocSupply(VBAT_Type *base)

Switch the RAM to be powered by Soc Supply in software mode.

Parameters

- base – VBAT peripheral base address.

static inline void VBAT_PowerOffSRAMsInLowPowerModes(VBAT_Type *base, uint8_t sramMask)

Power off selected SRAM array in low power modes.

Parameters

- base – VBAT peripheral base address.
- sramMask – The mask of SRAM array to power off, should be the OR'ed value of *vbat_ram_array_t*.

static inline void VBAT_RetainSRAMsInLowPowerModes(VBAT_Type *base, uint8_t sramMask)

Retain selected SRAM array in low power modes.

Parameters

- base – VBAT peripheral base address.
- sramMask – The mask of SRAM array to retain, should be the OR'ed value of *vbat_ram_array_t*.

static inline void VBAT_EnableSRAMIsolation(VBAT_Type *base, bool enable)

Enable/disable SRAM isolation.

Parameters

- base – VBAT peripheral base address.
- enable – Used to enable/disable SRAM violation.

- **true** SRAM will be isolated.
- **false** SRAM state follows the SoC power modes.

status_t VBAT_EnableBandgapTimer(VBAT_Type *base, bool enable, uint8_t timerIdMask)

Enable/disable Bandgap timer.

Note: The bandgap timer is available when the bandgap is enabled and are clocked by the FRO16k.

Parameters

- base – VBAT peripheral base address.
- enable – Used to enable/disable bandgap timer.
- timerIdMask – The mask of bandgap timer Id, should be the OR'ed value of *vbat_bandgap_timer_id_t*.

Return values

- kStatus_Success – Success to enable/disable selected bandgap timer.
- kStatus_VBAT_Fro16kNotEnabled – Fail to enable/disable selected bandgap timer due to FRO16k not enabled previously.
- kStatus_VBAT_BandgapNotEnabled – Fail to enable/disable selected bandgap timer due to bandgap not enabled previously.

void VBAT_SetBandgapTimer0TimeoutValue(VBAT_Type *base, *vbat_bandgap_timer0_timeout_period_t* timeoutPeriod)

Set bandgap timer0 timeout value.

Note: The timeout value can only be changed when the timer is disabled.

Parameters

- base – VBAT peripheral base address.
- timeoutPeriod – Bandgap timer timeout value, please refer to *vbat_bandgap_timer0_timeout_period_t*.

void VBAT_SetBandgapTimer1TimeoutValue(VBAT_Type *base, uint32_t timeoutPeriod)

Set bandgap timer1 timeout value.

Note: The timeout value can only be changed when the timer is disabled.

Parameters

- base – VBAT peripheral base address.
- timeoutPeriod – The bandgap timerout 1 period, in number of seconds, ranging from 0 to 65535s.

static inline void VBAT_SwitchVBATModuleSupplyActiveMode(VBAT_Type *base, *vbat_internal_module_supply_t* supply)

Control the VBAT internal switch in active mode, VBAT modules can be suppiled by VDD_BAT and VDD_SYS.

Parameters

- base – VBAT peripheral base address.
- supply – Used to control the VBAT internal switch.

static inline *vbat_internal_module_supply_t* VBAT_GetVBATModuleSupply(VBAT_Type *base)

Get VBAT module supply in active mode.

Parameters

- base – VBAT peripheral base address.

Returns

VDD_SYS supplies VBAT modules or VDD_BAT supplies VBAT modules, in type of *vbat_internal_module_supply_t*.

static inline void VBAT_SwitchVBATModuleSupplyLowPowerMode(VBAT_Type *base, *vbat_internal_module_supply_t* supply)

Control the VBAT internal switch in low power modes.

Note: If VBAT modules are supplied by VDD_SYS in low power modes, VBAT module will also supplied by VDD_SYS in active mode.

Parameters

- base – VBAT peripheral base address.
- supply – Used to specify which voltage input supply VBAT modules in low power mode.

static inline void VBAT_LockSwitchControl(VBAT_Type *base)

Lock switch control, if locked all writes to the switch registers will be blocked.

Parameters

- base – VBAT peripheral base address.

static inline void VBAT_UnlockSwitchControl(VBAT_Type *base)

Unlock switch control.

Parameters

- base – VBAT peripheral base address.

static inline bool VBAT_CheckSwitchControlLocked(VBAT_Type *base)

Check if switch control is locked.

Parameters

- base – VBAT peripheral base address.

Return values

- false – switch control is not locked.
- true – switch control is locked, any writes to related registers are blocked.

status_t VBAT_InitClockMonitor(VBAT_Type *base, const *vbat_clock_monitor_config_t* *config)

Initialize the VBAT clock monitor, enable clock monitor and set the clock monitor configuration.

Note: Both FRO16K and OSC32K should be enabled and stable before invoking this function.

Parameters

- base – VBAT peripheral base address.
- config – Pointer to *vbat_clock_monitor_config_t* structure.

Return values

- kStatus_Success – Clock monitor is initialized successfully.
- kStatus_VBAT_Fro16kNotEnabled – FRO16K is not enabled.
- kStatus_VBAT_Osc32kNotReady – OSC32K is not ready.
- kStatus_VBAT_ClockMonitorLocked – Clock monitor is locked.

status_t VBAT_DeinitMonitor(VBAT_Type *base)

Deinitialize the VBAT clock monitor.

Parameters

- base – VBAT peripheral base address.

Return values

- kStatus_Success – Clock monitor is de-initialized successfully.
- kStatus_VBAT_ClockMonitorLocked – Control of Clock monitor is locked.

static inline void VBAT_EnableClockMonitor(VBAT_Type *base, bool enable)

Enable/disable clock monitor.

- false: disable clock monitor.

Parameters

- base – VBAT peripheral base address.
- enable – Switcher to enable/disable clock monitor:
  - true: enable clock monitor;

static inline void VBAT_SetClockMonitorDivideTrim(VBAT_Type *base, *vbat_clock_monitor_divide_trim_t* divideTrim)

Set clock monitor's divide trim, avaiable value is *kVBAT_ClockMonitorOperateAt1kHz* and *kVBAT_ClockMonitorOperateAt64Hz*.

Parameters

- base – VBAT peripheral base address.
- divideTrim – Specify divide trim value, please refer to *vbat_clock_monitor_divide_trim_t*.

static inline void VBAT_SetClockMonitorFrequencyTrim(VBAT_Type *base, *vbat_clock_monitor_freq_trim_t* freqTrim)

Set clock monitor's frequency trim, avaiable value is *kVBAT_ClockMonitorAssert2Cycle*, *kVBAT_ClockMonitorAssert4Cycle*, *kVBAT_ClockMonitorAssert6Cycle* and *kVBAT_ClockMonitorAssert8Cycle*.

Parameters

- base – VBAT peripheral base address.
- freqTrim – Specify frequency trim value, please refer to *vbat_clock_monitor_freq_trim_t*.

static inline void VBAT_LockClockMonitorControl(VBAT_Type *base)

Lock clock monitor enable/disable control.

Note: If locked, it is not allowed to change clock monitor enable/disable control.

Parameters

- base – VBAT peripheral base address.

static inline void VBAT_UnlockClockMonitorControl(VBAT_Type *base)

Unlock clock monitor enable/disable control.

Parameters

- base – VBTA peripheral base address.

static inline bool VBAT_CheckClockMonitorControlLocked(VBAT_Type *base)

Check if clock monitor enable/disable control is locked.

Note: If locked, it is not allowed to change clock monitor enable/disable control.

Parameters

- base – VBAT peripheral base address.

Return values

- false – clock monitor enable/disable control is not locked.
- true – clock monitor enable/disable control is locked, any writes to related registers are blocked.

status_t VBAT_InitTamper(VBAT_Type *base, const *vbat_tamper_config_t* *config)

Initialize tamper control.

Note: Both FRO16K and bandgap should be enabled before calling this function.

Parameters

- base – VBAT peripheral base address.
- config – Pointer to *vbat_tamper_config_t* structure.

Return values

- kStatus_Success – Tamper is initialized successfully.

- kStatus_VBAT_TamperLocked – Tamper control is locked.
- kStatus_VBAT_BandgapNotEnabled – Bandgap is not enabled.
- kStatus_VBAT_Fro16kNotEnabled – FRO 16K is not enabled.

status_t VBAT_DeinitTamper(VBAT_Type *base)

De-initialize tamper control.

Parameters

- base – VBAT peripheral base address.

Return values

- kStatus_Success – Tamper is de-initialized successfully.
- kStatus_VBAT_TamperLocked – Tamper control is locked.

static inline void VBAT_EnableTamper(VBAT_Type *base, uint32_t tamperEnableMask)

Enable tampers for VBAT.

Parameters

- base – VBAT peripheral base address.
- tamperEnableMask – Mask of tamper to be enabled, should be the OR'ed value of *_vbat_tamper_enable*.

static inline void VBAT_DisableTamper(VBAT_Type *base, uint32_t tamperEnableMask)

Disable tampers for VBAT.

Parameters

- base – VBAT peripheral base address.
- tamperEnableMask – Mask of tamper to be disabled, should be the OR'ed value of *_vbat_tamper_enable*.

static inline uint32_t VBAT_GetTamperEnableInfo(VBAT_Type *base)

Get tamper enable information.

Parameters

- base – VBAT peripheral base address.

Returns

Mask of tamper enable information, should be the OR'ed value of *_vbat_tamper_enable*.

static inline void VBAT_LockTamperControl(VBAT_Type *base)

Lock tamper control, if locked, it is not allowed to change tamper control.

Parameters

- base – VBAT peripheral base address.

static inline void VBAT_UnlockTamperControl(VBAT_Type *base)

Unlock tamper control.

Parameters

- base – VBAT peripheral base address.

static inline bool VBAT_CheckTamperControlLocked(VBAT_Type *base)

Check if tamper control is locked.

Parameters

- base – VBAT peripheral base address.

Return values

- false – Tamper control is not locked.
- true – Tamper control is locked, any writes to related registers are blocked.

static inline uint32_t VBAT_GetStatusFlags(VBAT_Type *base)

Get VBAT status flags.

Parameters

- base – VBAT peripheral base address.

Returns

The asserted status flags, should be the OR'ed value of *vbat_status_flag_t*.

static inline void VBAT_ClearStatusFlags(VBAT_Type *base, uint32_t mask)

Clear VBAT status flags.

Parameters

- base – VBAT peripheral base address.
- mask – The mask of status flags to be cleared, should be the OR'ed value of *vbat_status_flag_t* except *kVBAT_StatusFlagLdoReady*, *kVBAT_StatusFlagOsc32kReady*, *kVBAT_StatusFlagInterrupt0Detect*, *kVBAT_StatusFlagInterrupt1Detect*, *kVBAT_StatusFlagInterrupt2Detect*, *kVBAT_StatusFlagInterrupt3Detect*.

static inline void VBAT_EnableInterrupts(VBAT_Type *base, uint32_t mask)

Enable interrupts for the VBAT module, such as POR detect interrupt, Wakeup Pin interrupt and so on.

Parameters

- base – VBAT peripheral base address.
- mask – The mask of interrupts to be enabled, should be the OR'ed value of *vbat_interrupt_enable_t*.

static inline void VBAT_DisableInterrupts(VBAT_Type *base, uint32_t mask)

Disable interrupts for the VBAT module, such as POR detect interrupt, wakeup pin interrupt and so on.

Parameters

- base – VBAT peripheral base address.
- mask – The mask of interrupts to be disabled, should be the OR'ed value of *vbat_interrupt_enable_t*.

static inline void VBAT_EnableWakeup(VBAT_Type *base, uint32_t mask)

Enable wakeup for the VBAT module, such as POR detect wakeup, wakeup pin wakeup and so on.

Parameters

- base – VBAT peripheral base address.
- mask – The mask of enumerators in *vbat_wakeup_enable_t*.

static inline void VBAT_DisableWakeup(VBAT_Type *base, uint32_t mask)

Disable wakeup for VBAT module, such as POR detect wakeup, wakeup pin wakeup and so on.

Parameters

- base – VBAT peripheral base address.
- mask – The mask of enumerators in *vbat_wakeup_enable_t*.

static inline void VBAT_LockInterruptWakeupSettings(VBAT_Type *base)

Lock VBAT interrupt and wakeup settings, please note that if locked the interrupt and wakeup settings can not be updated until the next POR.

Parameters

- base – VBAT peripheral base address.

static inline void VBAT_SetWakeupPinDefaultState(VBAT_Type *base, bool assert)

Set the default state of the WAKEUP_b pin output when no enabled wakeup source is asserted.

Parameters

- base – VBAT peripheral base address.
- assert – Used to set default state of the WAKEUP_b pin output:
  - **true** WAKEUP_b output state is logic one;
  - **false** WAKEUP_b output state is logic zero.

struct _vbat_fro16k_config

#include <fsl_vbat.h> The structure of internal 16kHz free running oscillator attributes.

Public Members

bool enableFRO16k

Enable/disable internal 16kHz free running oscillator.

uint8_t enabledConnectionsMask

The mask of connected modules to enable FRO16k clock output.

struct _vbat_clock_monitor_config

#include <fsl_vbat.h> The structure of internal clock monitor, including divide trim and frequency trim.

Public Members

vbat_clock_monitor_freq_trim_t freqTrim

Frequency trim value used to adjust the clock monitor assert, please refer to *vbat_clock_monitor_freq_trim_t*.

bool lock

Lock the clock monitor control after enabled.

struct _vbat_tamper_config

#include <fsl_vbat.h> The structure of Tamper configuration.

Public Members

bool enableVoltageDetect
Enable/disable voltage detection.

bool enableTemperatureDetect
Enable/disable temperature detection.

bool lock
Lock the tamper control after enabled.

2.64 OPAMP: Operational Amplifier

void OPAMP_Init(OPAMP_Type *base, const *opamp_config_t* *config)
Initialize OPAMP instance.

Parameters

- base – OPAMP peripheral base address.
- config – The pointer to *opamp_config_t*.

void OPAMP_Deinit(OPAMP_Type *base)
De-initialize OPAMP instance.

Parameters

- base – OPAMP peripheral base address.

void OPAMP_GetDefaultConfig(*opamp_config_t* *config)
Get default configuration of OPAMP.

```
config->enable      = false;
config->compCap     = kOPAMP_FitGain2x;
config->biasCurrent = kOPAMP_NoChange;
```

Parameters

- config – The pointer to *opamp_config_t*.

static inline void OPAMP_SetCompensationCapcitor(OPAMP_Type *base, uint8_t compCap)
This function is used to set OPAMP compensation capcitor.

Parameters

- base – OPAMP peripheral base address.
- compCap – The value of compensation capcitor.

static inline void OPAMP_SetBiasCurrent(OPAMP_Type *base, uint8_t biasCurrent)
This function is used to set the OPAMP bias current.

Parameters

- base – OPAMP peripheral base address.
- biasCurrent – The value of bias current.

static inline void OPAMP_Enable(OPAMP_Type *base, bool enable)
This function is used to enable or disable the OPAMP.

Parameters

- base – OPAMP peripheral base address.

- enable – Decides whether to enable or disable the OPAMP.
  - **true** Enable the OPAMP.
  - **false** DIsable the OPAMP.

FSL_OPAMP_DRIVER_VERSION

OPAMP driver version.

enum _opamp_comp_cap

The enumeration provides the selection of the OPAMP compensation capcitor, choose different option to fit different gains.

Values:

enumerator kOPAMP_FitGain2x

Fit 2x gains.

enumerator kOPAMP_FitGain4x

Fit 4x gains.

enumerator kOPAMP_FitGain8x

Fit 2x gains.

enumerator kOPAMP_FitGain16x

Fit 16x gains.

enum _opamp_bias_current

The enumeration provides the selection of the OPAMP bias current, choose different option to change power comsumption.

Values:

enumerator kOPAMP_NoChange

Keep power consumption constant.

enumerator kOPAMP_ChangeToQuarter

Reduce power consumption to 1/4.

enumerator kOPAMP_ChangeToHalf

Reduce power consumption to 1/2.

enumerator kOPAMP_ChangeToDouble

Double the power consumption.

typedef enum *_opamp_comp_cap* opamp_comp_cap_t

The enumeration provides the selection of the OPAMP compensation capcitor, choose different option to fit different gains.

typedef enum *_opamp_bias_current* opamp_bias_current_t

The enumeration provides the selection of the OPAMP bias current, choose different option to change power comsumption.

typedef struct *_opamp_config* opamp_config_t
OPAMP configuraion.

struct _opamp_config
#include <fsl_opamp.h> OPAMP configuraion.

Public Members

bool enable
Decides whether to enable or disable OPAMP.

uint8_t compCap
Compensation capacitor selection.

uint8_t biasCurrent
Bias current selection.

2.65 OSTIMER: OS Event Timer Driver

void OSTIMER_Init(OSTIMER_Type *base)
Initializes an OSTIMER by turning its bus clock on.

void OSTIMER_Deinit(OSTIMER_Type *base)
Deinitializes a OSTIMER instance.

This function shuts down OSTIMER bus clock

Parameters

- base – OSTIMER peripheral base address.

uint64_t OSTIMER_GrayToDecimal(uint64_t gray)
Translate the value from gray-code to decimal.

Parameters

- gray – The gray value input.

Returns
The decimal value.

static inline uint64_t OSTIMER_DecimalToGray(uint64_t dec)
Translate the value from decimal to gray-code.

Parameters

- dec – The decimal value.

Returns
The gray code of the input value.

uint32_t OSTIMER_GetStatusFlags(OSTIMER_Type *base)
Get OSTIMER status Flags.

This returns the status flag. Currently, only match interrupt flag can be got.

Parameters

- base – OSTIMER peripheral base address.

Returns
status register value

void OSTIMER_ClearStatusFlags(OSTIMER_Type *base, uint32_t mask)

Clear Status Interrupt Flags.

This clears interrupt status flag. Currently, only match interrupt flag can be cleared.

Parameters

- base – OSTIMER peripheral base address.
- mask – Clear bit mask.

Returns
none

status_t OSTIMER_SetMatchRawValue(OSTIMER_Type *base, uint64_t count, *ostimer_callback_t* cb)

Set the match raw value for OSTIMER.

This function will set a match value for OSTIMER with an optional callback. And this callback will be called while the data in dedicated pair match register is equals to the value of central EVTIMER. Please note that, the data format may be gray-code, if so, please use *OSTIMER_SetMatchValue()*.

Parameters

- base – OSTIMER peripheral base address.
- count – OSTIMER timer match value.(Value may be gray-code format)
- cb – OSTIMER callback (can be left as NULL if none, otherwise should be a void func(void)).

Return values
kStatus_Success – Match raw value written and interrupt enabled successfully.

status_t OSTIMER_SetMatchValue(OSTIMER_Type *base, uint64_t count, *ostimer_callback_t* cb)

Set the match value for OSTIMER.

This function will set a match value for OSTIMER with an optional callback. And this callback will be called while the data in dedicated pair match register is equals to the value of central EVTIMER.

The function disables the match interrupt before writing the match registers and re-enables it immediately after. This function is suitable when the delta between the current timer value and count is comfortably larger than the match-register synchronisation latency (more than 7 OSTimer ticks). However, it does NOT wait for OSEVENT_CTRL[MATCH_WR_RDY]) after writing MATCH, and it does NOT check whether the requested match time has already passed. If there is any possibility that count is close to or has already passed the current timer value, use *OSTIMER_SetMatchValueSafe()* instead, which polls MATCH_WR_RDY and checks whether the match moment has been missed.

Parameters

- base – OSTIMER peripheral base address.
- count – Match value in decimal (binary) format. The driver converts to Gray code internally when the hardware counter is Gray-encoded.
- cb – OSTIMER callback (can be left as NULL if none, otherwise should be a void func(void)).

Return values
kStatus_Success – Match value written and interrupt enabled successfully.

status_t OSTIMER_SetMatchValueSafe(OSTIMER_Type *base, uint64_t count, *ostimer_callback_t* cb)

Set the match value for OSTIMER with full synchronisation and missed-event detection.

This function will set a match value for OSTIMER with an optional callback. And this callback will be called while the data in dedicated pair match register is equals to the value of central EVTIMER.

Unlike *OSTIMER_SetMatchValue()*, this function performs the following additional steps after writing the match registers:

a. Wait for write synchronisation (MATCH_WR_RDY). On devices that expose OSEVENT_CTRL[MATCH_WR_RDY], the function spins until that bit is cleared, which indicates that the written value has been transferred from the shadow registers to the active compare registers in the OSTimer clock domain. This eliminates the race condition where the timer advances past the match value before the hardware has latched it.

b. Check whether the match moment has already been missed. After MATCH_WR_RDY clears, the function reads the current timer value and compares it with count:

   - If the current timer value is still below count, the match has not yet occurred. The interrupt is enabled and the function returns *kStatus_Success*.
   - If the current timer value has reached or passed count:
     - If the hardware interrupt flag (OSTIMER_INTRFLAG) is already set, the match event was captured by hardware. The interrupt is enabled so the pending flag triggers the ISR, and the function returns *kStatus_Success*.
     - If the interrupt flag is NOT set, the match moment passed without the hardware capturing it (the compare logic had not yet latched the value when the timer advanced). The interrupt is left DISABLED and the function returns *kStatus_Fail*. The caller is responsible for handling this missed event, for example by scheduling a new match immediately or executing the intended action directly.

Note: This function is recommended whenever the requested match delta is small or unpredictable relative to the OSTimer source clock period. If the overhead of polling MATCH_WR_RDY is unacceptable (e.g. at 32 KHz with tight real-time constraints), use *OSTIMER_SetMatchValue()* and ensure the match delta is always large enough.

Parameters

- base – OSTIMER peripheral base address.
- count – Match value in decimal (binary) format. The driver converts to Gray code internally when the hardware counter is Gray-encoded.
- cb – OSTIMER callback (can be left as NULL if none, otherwise should be a void func(void)).

Return values

- kStatus_Success – Match value written and interrupt enabled. The match event will occur in the future, or the hardware interrupt flag was already set and the pending interrupt will fire immediately upon enabling.
- kStatus_Fail – Match time already passed and the hardware interrupt flag was not set. The interrupt remains disabled. The caller must handle the missed event.

static inline void OSTIMER_SetMatchRegister(OSTIMER_Type *base, uint64_t value)

Set value to OSTIMER MATCH register directly.

This function writes the input value to OSTIMER MATCH register directly, it does not touch any other registers. Note that, the data format is gray-code if the hardware register is gray-encoded. The function *OSTIMER_DecimalToGray* could convert decimal value to gray code.

Parameters

- base – OSTIMER peripheral base address.
- value – OSTIMER timer match value (Value is gray-code format if the hardware register is gray-encoded).

static inline uint64_t OSTIMER_GetMatchRegister(OSTIMER_Type *base)

Get the match value from OSTIMER.

This function will get the match value from OSTIMER. The value of timer match is gray code format if the hardware is Gray-encoded.

Parameters

- base – OSTIMER peripheral base address.

Returns

Value of match register, data format is gray code if the register is Gray-encoded.

static inline uint64_t OSTIMER_GetMatchValue(OSTIMER_Type *base)

Get the match value from OSTIMER.

This function will get a match value from OSTIMER.

Parameters

- base – OSTIMER peripheral base address.

Returns

Value of match register in decimal format.

static inline void OSTIMER_EnableMatchInterrupt(OSTIMER_Type *base)

Enable the OSTIMER counter match interrupt.

Enable the timer counter match interrupt. The interrupt happens when OSTIMER counter matches the value in MATCH registers.

Parameters

- base – OSTIMER peripheral base address.

static inline void OSTIMER_DisableMatchInterrupt(OSTIMER_Type *base)

Disable the OSTIMER counter match interrupt.

Disable the timer counter match interrupt. The interrupt happens when OSTIMER counter matches the value in MATCH registers.

Parameters

- base – OSTIMER peripheral base address.

static inline uint64_t OSTIMER_GetCurrentTimerRawValue(OSTIMER_Type *base)

Get current timer raw count value from OSTIMER.

This function will get the timer count value from OS timer register. The raw value of timer count may be gray code format.

Parameters

- base – OSTIMER peripheral base address.

Returns
Raw value of OSTIMER, may be gray code format if the hardware register is Gray-encoded.

uint64_t OSTIMER_GetCurrentTimerValue(OSTIMER_Type *base)

Get current timer count value from OSTIMER.

This function will get a decimal timer count value. If the RAW value of timer count is gray code format, it will be translated to decimal data internally.

Parameters
- base – OSTIMER peripheral base address.

Returns
Value of OSTIMER which will be formated to decimal value.

static inline uint64_t OSTIMER_GetCaptureRawValue(OSTIMER_Type *base)

Get the capture value from OSTIMER.

This function will get a captured value from OSTIMER. The Raw value of timer capture may be gray code format if the hardware register is Gray-encoded.

Parameters
- base – OSTIMER peripheral base address.

Returns
Raw value of capture register, data format may be gray code if the hardware register is Gray-encoded.

uint64_t OSTIMER_GetCaptureValue(OSTIMER_Type *base)

Get the capture value from OSTIMER.

This function will get a capture decimal-value from OSTIMER. If the RAW value of timer count is gray code format, it will be translated to decimal data internally.

Parameters
- base – OSTIMER peripheral base address.

Returns
Value of capture register, data format is decimal.

void OSTIMER_HandleIRQ(OSTIMER_Type *base, *ostimer_callback_t* cb)

OS timer interrupt Service Handler.

This function handles the interrupt and refers to the callback array in the driver to callback user (as per request in *OSTIMER_SetMatchValue()*). if no user callback is scheduled, the interrupt will simply be cleared.

Parameters
- base – OS timer peripheral base address.
- cb – callback scheduled for this instance of OS timer

Returns
none

void OSTIMER_DriverIRQHandler(uint32_t instance)

OSTIMER parameterized IRQ handler entry.

Parameters
- instance – OSTIMER instance index.

FSL_OSTIMER_DRIVER_VERSION
OSTIMER driver version.

enum _ostimer_flags
OSTIMER status flags.

Values:

enumerator kOSTIMER_MatchInterruptFlag
Match interrupt flag bit, sets if the match value was reached.

typedef void (*ostimer_callback_t)(void)
ostimer callback function.

2.66 PORT: Port Control and Interrupts

static inline void PORT_GetVersionInfo(PORT_Type *base, *port_version_info_t* *info)
Get PORT version information.

Parameters

- base – PORT peripheral base pointer
- info – PORT version information

static inline void PORT_SecletPortVoltageRange(PORT_Type *base, *port_voltage_range_t* range)
Get PORT version information.

Note: : PORTA_CONFIG[RANGE] controls the voltage ranges of Port A, B, and C. Read or write PORTB_CONFIG[RANGE] and PORTC_CONFIG[RANGE] does not take effect.

Parameters

- base – PORT peripheral base pointer
- range – port voltage range

static inline void PORT_SetPinConfig(PORT_Type *base, uint32_t pin, const *port_pin_config_t* *config)
Sets the port PCR register.

This is an example to define an input pin or output pin PCR configuration.

```
// Define a digital input pin PCR configuration
port_pin_config_t config = {
    kPORT_PullUp,
    kPORT_FastSlewRate,
    kPORT_PassiveFilterDisable,
    kPORT_OpenDrainDisable,
    kPORT_LowDriveStrength,
    kPORT_MuxAsGpio,
    kPORT_UnLockRegister,
};
```

Parameters

- base – PORT peripheral base pointer.
- pin – PORT pin number.
- config – PORT PCR register configuration structure.

static inline void PORT_SetMultiplePinsConfig(PORT_Type *base, uint32_t mask, const *port_pin_config_t* *config)

Sets the port PCR register for multiple pins.

This is an example to define input pins or output pins PCR configuration.

```
Define a digital input pin PCR configuration
port_pin_config_t config = {
    kPORT_PullUp ,
    kPORT_PullEnable,
    kPORT_FastSlewRate,
    kPORT_PassiveFilterDisable,
    kPORT_OpenDrainDisable,
    kPORT_LowDriveStrength,
    kPORT_MuxAsGpio,
    kPORT_UnlockRegister,
};
```

Parameters

- base – PORT peripheral base pointer.
- mask – PORT pin number macro.
- config – PORT PCR register configuration structure.

static inline void PORT_SetPinMux(PORT_Type *base, uint32_t pin, *port_mux_t* mux)

Configures the pin muxing.

Note: : This function is NOT recommended to use together with the PORT_SetPinsConfig, because the PORT_SetPinsConfig need to configure the pin mux anyway (Otherwise the pin mux is reset to zero : kPORT_PinDisabledOrAnalog). This function is recommended to use to reset the pin mux

---

Parameters

- base – PORT peripheral base pointer.
- pin – PORT pin number.
- mux – pin muxing slot selection.
  - *kPORT_PinDisabledOrAnalog*: Pin disabled or work in analog function.
  - *kPORT_MuxAsGpio* : Set as GPIO.
  - *kPORT_MuxAlt2* : chip-specific.
  - *kPORT_MuxAlt3* : chip-specific.
  - *kPORT_MuxAlt4* : chip-specific.
  - *kPORT_MuxAlt5* : chip-specific.
  - *kPORT_MuxAlt6* : chip-specific.
  - *kPORT_MuxAlt7* : chip-specific.

static inline void PORT_EnablePinsDigitalFilter(PORT_Type *base, uint32_t mask, bool enable)

Enables the digital filter in one port, each bit of the 32-bit register represents one pin.

Parameters

- base – PORT peripheral base pointer.
- mask – PORT pin number macro.
- enable – PORT digital filter configuration.

static inline void PORT_SetDigitalFilterConfig(PORT_Type *base, const *port_digital_filter_config_t* *config)

Sets the digital filter in one port, each bit of the 32-bit register represents one pin.

Parameters

- base – PORT peripheral base pointer.
- config – PORT digital filter configuration structure.

static inline void PORT_SetPinDriveStrength(PORT_Type *base, uint32_t pin, uint8_t strength)

Configures the port pin drive strength.

Parameters

- base – PORT peripheral base pointer.
- pin – PORT pin number.
- strength – PORT pin drive strength
  - *kPORT_LowDriveStrength* = 0U - Low-drive strength is configured.
  - *kPORT_HighDriveStrength* = 1U - High-drive strength is configured.

static inline void PORT_EnablePinDoubleDriveStrength(PORT_Type *base, uint32_t pin, bool enable)

Enables the port pin double drive strength.

Parameters

- base – PORT peripheral base pointer.
- pin – PORT pin number.
- enable – PORT pin drive strength configuration.

static inline void PORT_SetPinPullValue(PORT_Type *base, uint32_t pin, uint8_t value)

Configures the port pin pull value.

Parameters

- base – PORT peripheral base pointer.
- pin – PORT pin number.
- value – PORT pin pull value
  - *kPORT_LowPullResistor* = 0U - Low internal pull resistor value is selected.
  - *kPORT_HighPullResistor* = 1U - High internal pull resistor value is selected.

static inline uint32_t PORT_GetEFTDetectFlags(PORT_Type *base)

Get EFT detect flags.

Parameters

- base – PORT peripheral base pointer

Returns
EFT detect flags

static inline void PORT_EnableEFTDetectInterrupts(PORT_Type *base, uint32_t interrupt)
Enable EFT detect interrupts.

Parameters

- base – PORT peripheral base pointer
- interrupt – EFT detect interrupt

static inline void PORT_DisableEFTDetectInterrupts(PORT_Type *base, uint32_t interrupt)
Disable EFT detect interrupts.

Parameters

- base – PORT peripheral base pointer
- interrupt – EFT detect interrupt

static inline void PORT_ClearAllLowEFTDetectors(PORT_Type *base)
Clear all low EFT detector.

Note: : Port B and Port C pins share the same EFT detector clear control from PORTC_EDCR register. Any write to the PORTB_EDCR does not take effect.

Parameters

- base – PORT peripheral base pointer

static inline void PORT_ClearAllHighEFTDetectors(PORT_Type *base)
Clear all high EFT detector.

Parameters

- base – PORT peripheral base pointer

FSL_PORT_DRIVER_VERSION
PORT driver version.

enum _port_pull
Internal resistor pull feature selection.
Values:

enumerator kPORT_PullDisable
Internal pull-up/down resistor is disabled.

enumerator kPORT_PullDown
Internal pull-down resistor is enabled.

enumerator kPORT_PullUp
Internal pull-up resistor is enabled.

enum _port_pull_value
Internal resistor pull value selection.
Values:

enumerator kPORT_LowPullResistor
Low internal pull resistor value is selected.

enumerator kPORT_HighPullResistor
High internal pull resistor value is selected.

enum _port_slew_rate
Slew rate selection.
Values:

enumerator kPORT_FastSlewRate
Fast slew rate is configured.

enumerator kPORT_SlowSlewRate
Slow slew rate is configured.

enum _port_open_drain_enable
Open Drain feature enable/disable.
Values:

enumerator kPORT_OpenDrainDisable
Open drain output is disabled.

enumerator kPORT_OpenDrainEnable
Open drain output is enabled.

enum _port_passive_filter_enable
Passive filter feature enable/disable.
Values:

enumerator kPORT_PassiveFilterDisable
Passive input filter is disabled.

enumerator kPORT_PassiveFilterEnable
Passive input filter is enabled.

enum _port_drive_strength
Configures the drive strength.
Values:

enumerator kPORT_LowDriveStrength
Low-drive strength is configured.

enumerator kPORT_HighDriveStrength
High-drive strength is configured.

enum _port_drive_strength1

Configures the drive strength1.

Values:

enumerator kPORT_NormalDriveStrength

Normal drive strength

enumerator kPORT_DoubleDriveStrength

Double drive strength

enum _port_input_buffer

input buffer disable/enable.

Values:

enumerator kPORT_InputBufferDisable

Digital input is disabled

enumerator kPORT_InputBufferEnable

Digital input is enabled

enum _port_invet_input

Digital input is not inverted or it is inverted.

Values:

enumerator kPORT_InputNormal

Digital input is not inverted

enumerator kPORT_InputInvert

Digital input is inverted

enum _port_lock_register

Unlock/lock the pin control register field[15:0].

Values:

enumerator kPORT_UnlockRegister

Pin Control Register fields [15:0] are not locked.

enumerator kPORT_LockRegister

Pin Control Register fields [15:0] are locked.

enum _port_mux

Pin mux selection.

Values:

enumerator kPORT_PinDisabledOrAnalog

Corresponding pin is disabled, but is used as an analog pin.

enumerator kPORT_MuxAsGpio
Corresponding pin is configured as GPIO.

enumerator kPORT_MuxAlt0
Chip-specific

enumerator kPORT_MuxAlt1
Chip-specific

enumerator kPORT_MuxAlt2
Chip-specific

enumerator kPORT_MuxAlt3
Chip-specific

enumerator kPORT_MuxAlt4
Chip-specific

enumerator kPORT_MuxAlt5
Chip-specific

enumerator kPORT_MuxAlt6
Chip-specific

enumerator kPORT_MuxAlt7
Chip-specific

enumerator kPORT_MuxAlt8
Chip-specific

enumerator kPORT_MuxAlt9
Chip-specific

enumerator kPORT_MuxAlt10
Chip-specific

enumerator kPORT_MuxAlt11
Chip-specific

enumerator kPORT_MuxAlt12
Chip-specific

enumerator kPORT_MuxAlt13
Chip-specific

enumerator kPORT_MuxAlt14
Chip-specific

enumerator kPORT_MuxAlt15
Chip-specific

enum _port_digital_filter_clock_source
Digital filter clock source selection.
Values:

enumerator kPORT_BusClock
Digital filters are clocked by the bus clock.

enumerator kPORT_LpoClock
Digital filters are clocked by the 1 kHz LPO clock.

enum _port_voltage_range
PORT voltage range.
Values:

enumerator kPORT_VoltageRange1Dot71V_3Dot6V
Port voltage range is 1.71 V - 3.6 V.

enumerator kPORT_VoltageRange2Dot70V_3Dot6V
Port voltage range is 2.70 V - 3.6 V.

typedef enum *_port_mux* port_mux_t
Pin mux selection.

typedef enum *_port_digital_filter_clock_source* port_digital_filter_clock_source_t
Digital filter clock source selection.

typedef struct *_port_digital_filter_config* port_digital_filter_config_t
PORT digital filter feature configuration definition.

typedef struct *_port_pin_config* port_pin_config_t
PORT pin configuration structure.

typedef struct *_port_version_info* port_version_info_t
PORT version information.

typedef enum *_port_voltage_range* port_voltage_range_t
PORT voltage range.

FSL_COMPONENT_ID

struct __port_digital_filter_config
#include <fsl_port.h> PORT digital filter feature configuration definition.

Public Members

uint32_t digitalFilterWidth
Set digital filter width

port_digital_filter_clock_source_t clockSource
Set digital filter clockSource

struct __port__pin__config
#include <fsl_port.h> PORT pin configuration structure.

Public Members

uint16_t pullSelect
No-pull/pull-down/pull-up select

uint16_t pullValueSelect
Pull value select

uint16_t slewRate
Fast/slow slew rate Configure

uint16_t passiveFilterEnable
Passive filter enable/disable

uint16_t openDrainEnable
Open drain enable/disable

uint16_t driveStrength
Fast/slow drive strength configure

uint16_t driveStrength1
Normal/Double drive strength enable/disable

uint16_t inputBuffer
Input Buffer Configure

uint16_t invertInput
Invert Input Configure

uint16_t lockRegister
Lock/unlock the PCR field[15:0]

struct __port__version__info
#include <fsl_port.h> PORT version information.

Public Members

uint16_t feature
: Feature Specification Number.

uint8_t minor
: Minor Version Number.

uint8_t major
: Major Version Number.

2.67 PWM: Pulse Width Modulator

status_t PWM_Init(PWM_Type *base, *pwm_submodule_t* subModule, const *pwm_config_t* *config)

Ungates the PWM submodule clock and configures the peripheral for basic operation.

This API should be called at the beginning of the application using the PWM driver. When user select PWMX, user must choose edge aligned output, becasue there are some limitation on center aligned PWMX output. When output PWMX in center aligned mode, VAL1 register controls both PWM period and PWMX duty cycle, PWMA and PWMB output will be corrupted. But edge aligned PWMX output do not have such limit. In master reload counter initialization mode, PWM period is depended by period of set LDOK in submodule 0 because this operation will reload register. Submodule 0 counter initialization cannot be master sync or master reload.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- config – Pointer to user's PWM config structure.

Returns
kStatus_Success means success; else failed.

void PWM_Deinit(PWM_Type *base, *pwm_submodule_t* subModule)

Gate the PWM submodule clock.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to deinitialize

void PWM_GetDefaultConfig(*pwm_config_t* *config)

Fill in the PWM config struct with the default settings.

The default values are:

```
config->enableDebugMode = false;
config->enableWait = false;
config->reloadSelect = kPWM_LocalReload;
config->clockSource = kPWM_BusClock;
config->prescale = kPWM_Prescale_Divide_1;
config->initializationControl = kPWM_Initialize_LocalSync;
config->forceTrigger = kPWM_Force_Local;
config->reloadFrequency = kPWM_LoadEveryOportunity;
```

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```
config->reloadLogic = kPWM_ReloadImmediate;
config->pairOperation = kPWM_Independent;
```

Parameters

- config – Pointer to user's PWM config structure.

status_t PWM_SetupPwm(PWM_Type *base, *pwm_submodule_t* subModule, const *pwm_signal_param_t* *chnlParams, uint8_t numOfChnls, *pwm_mode_t* mode, uint32_t pwmFreq_Hz, uint32_t srcClock_Hz)

Sets up the PWM signals for a PWM submodule.

The function initializes the submodule according to the parameters passed in by the user. The function also sets up the value compare registers to match the PWM signal requirements. If the dead time insertion logic is enabled, the pulse period is reduced by the dead time period specified by the user. When user select PWMX, user must choose edge aligned output, becasue there are some limitation on center aligned PWMX output. Due to edge aligned PWMX is negative true signal, need to configure PWMX active low true level to get correct duty cycle. The half cycle point will not be exactly in the middle of the PWM cycle when PWMX enabled.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- chnlParams – Array of PWM channel parameters to configure the channel(s).
- numOfChnls – Number of channels to configure, this should be the size of the array passed in. Array size should not be more than 3 as each submodule has 3 pins to output PWM.
- mode – PWM operation mode, options available in enumeration *pwm_mode_t*
- pwmFreq_Hz – PWM signal frequency in Hz
- srcClock_Hz – PWM source clock of correspond submodule in Hz. If source clock of submodule1,2,3 is from submodule0 AUX_CLK, its source clock is submodule0 source clock divided with submodule0 prescaler value instead of submodule0 source clock.

Returns

Returns kStatus_Fail if there was error setting up the signal; kStatus_Success otherwise

status_t PWM_SetupPwmPhaseShift(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_channels_t* pwmChannel, uint32_t pwmFreq_Hz, uint32_t srcClock_Hz, uint8_t shiftvalue, bool doSync)

Set PWM phase shift for PWM channel running on channel PWM_A, PWM_B which with 50% duty cycle.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- pwmChannel – PWM channel to configure
- pwmFreq_Hz – PWM signal frequency in Hz
- srcClock_Hz – PWM main counter clock in Hz.

- shiftvalue – Phase shift value, range in 0 ~ 50
- doSync – true: Set LDOK bit for the submodule list; false: LDOK bit don't set, need to call PWM_SetPwmLdok to sync update.

Returns

Returns kStatus_Fail if there was error setting up the signal; kStatus_Success otherwise

void PWM_UpdatePwmDutycycle(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_channels_t* pwmSignal, *pwm_mode_t* currPwmMode, uint8_t dutyCyclePercent)

Updates the PWM signal's dutycycle.

The function updates the PWM dutycyle to the new value that is passed in. If the dead time insertion logic is enabled then the pulse period is reduced by the dead time period specified by the user.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- pwmSignal – Signal (PWM A, PWM B, PWM X) to update
- currPwmMode – The current PWM mode set during PWM setup
- dutyCyclePercent – New PWM pulse width, value should be between 0 to 100 0=inactive signal(0% duty cycle)... 100=active signal (100% duty cycle)

void PWM_UpdatePwmDutycycleHighAccuracy(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_channels_t* pwmSignal, *pwm_mode_t* currPwmMode, uint16_t dutyCycle)

Updates the PWM signal's dutycycle with 16-bit accuracy.

The function updates the PWM dutycyle to the new value that is passed in. If the dead time insertion logic is enabled then the pulse period is reduced by the dead time period specified by the user.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- pwmSignal – Signal (PWM A, PWM B, PWM X) to update
- currPwmMode – The current PWM mode set during PWM setup
- dutyCycle – New PWM pulse width, value should be between 0 to 65535 0=inactive signal(0% duty cycle)... 65535=active signal (100% duty cycle)

void PWM_UpdatePwmPeriodAndDutycycle(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_channels_t* pwmSignal, *pwm_mode_t* currPwmMode, uint16_t pulseCnt, uint16_t dutyCycle)

Update the PWM signal's period and dutycycle for a PWM submodule.

The function updates PWM signal period generated by a specific submodule according to the parameters passed in by the user. This function can also set dutycycle weather you want to keep original dutycycle or update new dutycycle. Call this function in local sync control mode because PWM period is depended by

INIT and VAL1 register of each submodule. In master sync initialization control mode, call this function to update INIT and VAL1 register of all submodule because PWM period is

depended by INIT and VAL1 register in submodule0. If the dead time insertion logic is enabled, the pulse period is reduced by the dead time period specified by the user. PWM signal will not be generated if its period is less than dead time duration.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- pwmSignal – Signal (PWM A or PWM B) to update
- currPwmMode – The current PWM mode set during PWM setup, options available in enumeration *pwm_mode_t*
- pulseCnt – New PWM period, value should be between 0 to 65535 0=minimum PWM period... 65535=maximum PWM period
- dutyCycle – New PWM pulse width of channel, value should be between 0 to 65535 0=inactive signal(0% duty cycle)... 65535=active signal (100% duty cycle) You can keep original duty cycle or update new duty cycle

static inline void PWM_EnableInterrupts(PWM_Type *base, *pwm_submodule_t* subModule, uint32_t mask)

Enables the selected PWM interrupts.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- mask – The interrupts to enable. This is a logical OR of members of the enumeration *pwm_interrupt_enable_t*

static inline void PWM_DisableInterrupts(PWM_Type *base, *pwm_submodule_t* subModule, uint32_t mask)

Disables the selected PWM interrupts.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- mask – The interrupts to enable. This is a logical OR of members of the enumeration *pwm_interrupt_enable_t*

static inline uint32_t PWM_GetEnabledInterrupts(PWM_Type *base, *pwm_submodule_t* subModule)

Gets the enabled PWM interrupts.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure

Returns

The enabled interrupts. This is the logical OR of members of the enumeration *pwm_interrupt_enable_t*

static inline void PWM_DMAFIFOWatermarkControl(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_watermark_control_t* pwm_watermark_control)

Capture DMA Enable Source Select.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- pwm_watermark_control – PWM FIFO watermark and control

static inline void PWM_DMACaptureSourceSelect(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_dma_source_select_t* pwm_dma_source_select)

Capture DMA Enable Source Select.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- pwm_dma_source_select – PWM capture DMA enable source select

static inline void PWM_EnableDMACapture(PWM_Type *base, *pwm_submodule_t* subModule, uint16_t mask, bool activate)

Enables or disables the selected PWM DMA Capture read request.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- mask – The DMA to enable or disable. This is a logical OR of members of the enumeration *pwm_dma_enable_t*
- activate – true: Enable DMA read request; false: Disable DMA read request

static inline void PWM_EnableDMAWrite(PWM_Type *base, *pwm_submodule_t* subModule, bool activate)

Enables or disables the PWM DMA write request.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- activate – true: Enable DMA write request; false: Disable DMA write request

static inline uint32_t PWM_GetStatusFlags(PWM_Type *base, *pwm_submodule_t* subModule)

Gets the PWM status flags.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure

Returns

The status flags. This is the logical OR of members of the enumeration *pwm_status_flags_t*

static inline void PWM_ClearStatusFlags(PWM_Type *base, *pwm_submodule_t* subModule, uint32_t mask)

Clears the PWM status flags.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure

- mask – The status flags to clear. This is a logical OR of members of the enumeration *pwm_status_flags_t*

static inline void PWM_StartTimer(PWM_Type *base, uint8_t subModulesToStart)

Starts the PWM counter for a single or multiple submodules.

Sets the Run bit which enables the clocks to the PWM submodule. This function can start multiple submodules at the same time.

Parameters

- base – PWM peripheral base address
- subModulesToStart – PWM submodules to start. This is a logical OR of members of the enumeration *pwm_module_control_t*

static inline void PWM_StopTimer(PWM_Type *base, uint8_t subModulesToStop)

Stops the PWM counter for a single or multiple submodules.

Clears the Run bit which resets the submodule's counter. This function can stop multiple submodules at the same time.

Parameters

- base – PWM peripheral base address
- subModulesToStop – PWM submodules to stop. This is a logical OR of members of the enumeration *pwm_module_control_t*

FSL_PWM_DRIVER_VERSION

Version 2.10.1

enum _pwm_submodule

List of PWM submodules.

Values:

enumerator kPWM_Module_0

Submodule 0

enumerator kPWM_Module_1

Submodule 1

enumerator kPWM_Module_2

Submodule 2

enum _pwm_channels

List of PWM channels in each module.

Values:

enumerator kPWM_PwmB

enumerator kPWM_PwmA

enumerator kPWM_PwmX

enum _pwm_value_register

List of PWM value registers.

Values:

enumerator kPWM_ValueRegister_0

PWM Value0 register

enumerator kPWM_ValueRegister_1

PWM Value1 register

enumerator kPWM_ValueRegister_2

PWM Value2 register

enumerator kPWM_ValueRegister_3

PWM Value3 register

enumerator kPWM_ValueRegister_4

PWM Value4 register

enumerator kPWM_ValueRegister_5

PWM Value5 register

enum _pwm_value_register_mask

List of PWM value registers mask.

Values:

enumerator kPWM_ValueRegisterMask_0

PWM Value0 register mask

enumerator kPWM_ValueRegisterMask_1

PWM Value1 register mask

enumerator kPWM_ValueRegisterMask_2

PWM Value2 register mask

enumerator kPWM_ValueRegisterMask_3

PWM Value3 register mask

enumerator kPWM_ValueRegisterMask_4

PWM Value4 register mask

enumerator kPWM_ValueRegisterMask_5

PWM Value5 register mask

enum _pwm_clock_source

PWM clock source selection.

Values:

enumerator kPWM_BusClock
Device specific IPBus clock, refer reference manual for frequency

enumerator kPWM_ExternalClock
EXT_CLK is used as the clock

enumerator kPWM_Submodule0Clock
Clock of the submodule 0 (AUX_CLK) is used as the source clock

enum __pwm_clock_prescale
PWM prescaler factor selection for clock source.
Values:

enumerator kPWM_Prescale_Divide_1
PWM clock frequency = fclk/1

enumerator kPWM_Prescale_Divide_2
PWM clock frequency = fclk/2

enumerator kPWM_Prescale_Divide_4
PWM clock frequency = fclk/4

enumerator kPWM_Prescale_Divide_8
PWM clock frequency = fclk/8

enumerator kPWM_Prescale_Divide_16
PWM clock frequency = fclk/16

enumerator kPWM_Prescale_Divide_32
PWM clock frequency = fclk/32

enumerator kPWM_Prescale_Divide_64
PWM clock frequency = fclk/64

enumerator kPWM_Prescale_Divide_128
PWM clock frequency = fclk/128

enum __pwm_force_output_trigger
Options that can trigger a PWM FORCE_OUT.
Values:

enumerator kPWM_Force_Local
The local force signal, CTRL2[FORCE], from the submodule is used to force updates

enumerator kPWM_Force_Master
The master force signal from submodule 0 is used to force updates

enumerator kPWM_Force_LocalReload
The local reload signal from this submodule is used to force updates without regard to the state of LDOK

enumerator kPWM_Force_MasterReload
The master reload signal from submodule 0 is used to force updates if LDOK is set

enumerator kPWM_Force_LocalSync
The local sync signal from this submodule is used to force updates

enumerator kPWM_Force_MasterSync
The master sync signal from submodule0 is used to force updates

enumerator kPWM_Force_External
The external force signal, EXT_FORCE, from outside the PWM module causes updates

enumerator kPWM_Force_ExternalSync
The external sync signal, EXT_SYNC, from outside the PWM module causes updates

enum _pwm_output_state
PWM channel output status.
Values:

enumerator kPWM_HighState
The output state of PWM channel is high

enumerator kPWM_LowState
The output state of PWM channel is low

enumerator kPWM_NormalState
The output state of PWM channel is normal

enumerator kPWM_InvertState
The output state of PWM channel is invert

enumerator kPWM_MaskState
The output state of PWM channel is mask

enum _pwm_init_source
PWM counter initialization options.
Values:

enumerator kPWM_Initialize_LocalSync
Local sync causes initialization

enumerator kPWM_Initialize_MasterReload
Master reload from submodule 0 causes initialization

enumerator kPWM_Initialize_MasterSync
Master sync from submodule 0 causes initialization

enumerator kPWM_Initialize_ExtSync
EXT_SYNC causes initialization

enum _pwm_load_frequency
PWM load frequency selection.
Values:

enumerator kPWM_LoadEveryOportunity
Every PWM opportunity

enumerator kPWM_LoadEvery2Oportunity
Every 2 PWM opportunities

enumerator kPWM_LoadEvery3Oportunity
Every 3 PWM opportunities

enumerator kPWM_LoadEvery4Oportunity
Every 4 PWM opportunities

enumerator kPWM_LoadEvery5Oportunity
Every 5 PWM opportunities

enumerator kPWM_LoadEvery6Oportunity
Every 6 PWM opportunities

enumerator kPWM_LoadEvery7Oportunity
Every 7 PWM opportunities

enumerator kPWM_LoadEvery8Oportunity
Every 8 PWM opportunities

enumerator kPWM_LoadEvery9Oportunity
Every 9 PWM opportunities

enumerator kPWM_LoadEvery10Oportunity
Every 10 PWM opportunities

enumerator kPWM_LoadEvery11Oportunity
Every 11 PWM opportunities

enumerator kPWM_LoadEvery12Oportunity
Every 12 PWM opportunities

enumerator kPWM_LoadEvery13Oportunity
Every 13 PWM opportunities

enumerator kPWM_LoadEvery14Oportunity
Every 14 PWM opportunities

enumerator kPWM_LoadEvery15Oportunity
Every 15 PWM opportunities

enumerator kPWM_LoadEvery16Oportunity
Every 16 PWM opportunities

enum _pwm_fault_input
List of PWM fault selections.
Values:

enumerator kPWM_Fault_0
Fault 0 input pin

enumerator kPWM_Fault_1
Fault 1 input pin

enumerator kPWM_Fault_2
Fault 2 input pin

enumerator kPWM_Fault_3
Fault 3 input pin

enum _pwm_fault_disable
List of PWM fault disable mapping selections.
Values:

enumerator kPWM_FaultDisable_0
Fault 0 disable mapping

enumerator kPWM_FaultDisable_1
Fault 1 disable mapping

enumerator kPWM_FaultDisable_2
Fault 2 disable mapping

enumerator kPWM_FaultDisable_3
Fault 3 disable mapping

enum _pwm_fault_channels
List of PWM fault channels.
Values:

enumerator kPWM_faultchannel_0

enum _pwm_input_capture_edge

PWM capture edge select.

Values:

enumerator kPWM_Disable

Disabled

enumerator kPWM_FallingEdge

Capture on falling edge only

enumerator kPWM_RisingEdge

Capture on rising edge only

enumerator kPWM_RiseAndFallEdge

Capture on rising or falling edge

enum _pwm_force_signal

PWM output options when a FORCE_OUT signal is asserted.

Values:

enumerator kPWM_UsePwm

Generated PWM signal is used by the deadtime logic.

enumerator kPWM_InvertedPwm

Inverted PWM signal is used by the deadtime logic.

enumerator kPWM_SoftwareControl

Software controlled value is used by the deadtime logic.

enumerator kPWM_UseExternal

PWM_EXTA signal is used by the deadtime logic.

enum _pwm_chnl_pair_operation

Options available for the PWM A & B pair operation.

Values:

enumerator kPWM_Independent

PWM A & PWM B operate as 2 independent channels

enumerator kPWM_ComplementaryPwmA

PWM A & PWM B are complementary channels, PWM A generates the signal

enumerator kPWM_ComplementaryPwmB

PWM A & PWM B are complementary channels, PWM B generates the signal

enum _pwm_register_reload

Options available on how to load the buffered-registers with new values.

Values:

enumerator kPWM_ReloadImmediate
Buffered-registers get loaded with new values as soon as LDOK bit is set

enumerator kPWM_ReloadPwmHalfCycle
Registers loaded on a PWM half cycle

enumerator kPWM_ReloadPwmFullCycle
Registers loaded on a PWM full cycle

enumerator kPWM_ReloadPwmHalfAndFullCycle
Registers loaded on a PWM half & full cycle

enum __pwm_fault_recovery_mode
Options available on how to re-enable the PWM output when recovering from a fault.
Values:

enumerator kPWM_NoRecovery
PWM output will stay inactive

enumerator kPWM_RecoverHalfCycle
PWM output re-enabled at the first half cycle

enumerator kPWM_RecoverFullCycle
PWM output re-enabled at the first full cycle

enumerator kPWM_RecoverHalfAndFullCycle
PWM output re-enabled at the first half or full cycle

enum __pwm_interrupt_enable
List of PWM interrupt options.
Values:

enumerator kPWM_CompareVal0InterruptEnable
PWM VAL0 compare interrupt

enumerator kPWM_CompareVal1InterruptEnable
PWM VAL1 compare interrupt

enumerator kPWM_CompareVal2InterruptEnable
PWM VAL2 compare interrupt

enumerator kPWM_CompareVal3InterruptEnable
PWM VAL3 compare interrupt

enumerator kPWM_CompareVal4InterruptEnable
PWM VAL4 compare interrupt

enumerator kPWM_CompareVal5InterruptEnable
PWM VAL5 compare interrupt

enumerator kPWM_CaptureX0InterruptEnable
PWM capture X0 interrupt

enumerator kPWM_CaptureX1InterruptEnable
PWM capture X1 interrupt

enumerator kPWM_CaptureB0InterruptEnable
PWM capture B0 interrupt

enumerator kPWM_CaptureB1InterruptEnable
PWM capture B1 interrupt

enumerator kPWM_CaptureA0InterruptEnable
PWM capture A0 interrupt

enumerator kPWM_CaptureA1InterruptEnable
PWM capture A1 interrupt

enumerator kPWM_ReloadInterruptEnable
PWM reload interrupt

enumerator kPWM_ReloadErrorInterruptEnable
PWM reload error interrupt

enumerator kPWM_Fault0InterruptEnable
PWM fault 0 interrupt

enumerator kPWM_Fault1InterruptEnable
PWM fault 1 interrupt

enumerator kPWM_Fault2InterruptEnable
PWM fault 2 interrupt

enumerator kPWM_Fault3InterruptEnable
PWM fault 3 interrupt

enum _pwm_status_flags
List of PWM status flags.
Values:

enumerator kPWM_CompareVal0Flag
PWM VAL0 compare flag

enumerator kPWM_CompareVal1Flag
PWM VAL1 compare flag

enumerator kPWM_CompareVal2Flag
PWM VAL2 compare flag

enumerator kPWM_CompareVal3Flag
PWM VAL3 compare flag

enumerator kPWM_CompareVal4Flag
PWM VAL4 compare flag

enumerator kPWM_CompareVal5Flag
PWM VAL5 compare flag

enumerator kPWM_CaptureX0Flag
PWM capture X0 flag

enumerator kPWM_CaptureX1Flag
PWM capture X1 flag

enumerator kPWM_CaptureB0Flag
PWM capture B0 flag

enumerator kPWM_CaptureB1Flag
PWM capture B1 flag

enumerator kPWM_CaptureA0Flag
PWM capture A0 flag

enumerator kPWM_CaptureA1Flag
PWM capture A1 flag

enumerator kPWM_ReloadFlag
PWM reload flag

enumerator kPWM_ReloadErrorFlag
PWM reload error flag

enumerator kPWM_RegUpdatedFlag
PWM registers updated flag

enumerator kPWM_Fault0Flag
PWM fault 0 flag

enumerator kPWM_Fault1Flag
PWM fault 1 flag

enumerator kPWM_Fault2Flag
PWM fault 2 flag

enumerator kPWM_Fault3Flag
PWM fault 3 flag

enum _pwm_dma_enable
List of PWM DMA options.
Values:

enumerator kPWM_CaptureX0DMAEnable
PWM capture X0 DMA

enumerator kPWM_CaptureX1DMAEnable
PWM capture X1 DMA

enumerator kPWM_CaptureB0DMAEnable
PWM capture B0 DMA

enumerator kPWM_CaptureB1DMAEnable
PWM capture B1 DMA

enumerator kPWM_CaptureA0DMAEnable
PWM capture A0 DMA

enumerator kPWM_CaptureA1DMAEnable
PWM capture A1 DMA

enum _pwm_dma_source_select
List of PWM capture DMA enable source select.
Values:

enumerator kPWM_DMARequestDisable
Read DMA requests disabled

enumerator kPWM_DMAWatermarksEnable
Exceeding a FIFO watermark sets the DMA read request

enumerator kPWM_DMALocalSync
A local sync (VAL1 matches counter) sets the read DMA request

enumerator kPWM_DMALocalReload
A local reload (STS[RF] being set) sets the read DMA request

enum _pwm_watermark_control
PWM FIFO Watermark AND Control.
Values:

enumerator kPWM_FIFOWatermarksOR
Selected FIFO watermarks are OR'ed together

enumerator kPWM_FIFOWatermarksAND
Selected FIFO watermarks are AND'ed together

enum _pwm_mode
PWM operation mode.
Values:

enumerator kPWM_SignedCenterAligned
Signed center-aligned

enumerator kPWM_CenterAligned
Unsigned cente-aligned

enumerator kPWM_SignedEdgeAligned
Signed edge-aligned

enumerator kPWM_EdgeAligned
Unsigned edge-aligned

enum _pwm_level_select
PWM output pulse mode, high-true or low-true.
Values:

enumerator kPWM_HighTrue
High level represents "on" or "active" state

enumerator kPWM_LowTrue
Low level represents "on" or "active" state

enum _pwm_fault_state
PWM output fault status.
Values:

enumerator kPWM_PwmFaultState0
Output is forced to logic 0 state prior to consideration of output polarity control.

enumerator kPWM_PwmFaultState1
Output is forced to logic 1 state prior to consideration of output polarity control.

enumerator kPWM_PwmFaultState2
Output is tristated.

enumerator kPWM_PwmFaultState3
Output is tristated.

enum _pwm_reload_source_select
PWM reload source select.
Values:

enumerator kPWM_LocalReload
The local reload signal is used to reload registers

enumerator kPWM_MasterReload
The master reload signal (from submodule 0) is used to reload

enum _pwm_fault_clear
PWM fault clearing options.
Values:

enumerator kPWM_Automatic
Automatic fault clearing

enumerator kPWM_ManualNormal
Manual fault clearing with no fault safety mode

enumerator kPWM_ManualSafety
Manual fault clearing with fault safety mode

enum _pwm_module_control
Options for submodule master control operation.
Values:

enumerator kPWM_Control_Module_0
Control submodule 0's start/stop,buffer reload operation

enumerator kPWM_Control_Module_1
Control submodule 1's start/stop,buffer reload operation

enumerator kPWM_Control_Module_2
Control submodule 2's start/stop,buffer reload operation

enumerator kPWM_Control_Module_3
Control submodule 3's start/stop,buffer reload operation

typedef enum *_pwm_submodule* pwm_submodule_t
List of PWM submodules.

typedef enum *_pwm_channels* pwm_channels_t
List of PWM channels in each module.

typedef enum *_pwm_value_register* pwm_value_register_t
List of PWM value registers.

typedef enum *_pwm_clock_source* pwm_clock_source_t
PWM clock source selection.

typedef enum *_pwm_clock_prescale* pwm_clock_prescale_t
PWM prescaler factor selection for clock source.

typedef enum *_pwm_force_output_trigger* pwm_force_output_trigger_t
Options that can trigger a PWM FORCE_OUT.

typedef enum *_pwm_output_state* pwm_output_state_t
PWM channel output status.

typedef enum *_pwm_init_source* pwm_init_source_t
PWM counter initialization options.

typedef enum *_pwm_load_frequency* pwm_load_frequency_t
PWM load frequency selection.

typedef enum *_pwm_fault_input* pwm_fault_input_t
List of PWM fault selections.

typedef enum *_pwm_fault_disable* pwm_fault_disable_t
List of PWM fault disable mapping selections.

typedef enum *_pwm_fault_channels* pwm_fault_channels_t
List of PWM fault channels.

typedef enum *_pwm_input_capture_edge* pwm_input_capture_edge_t
PWM capture edge select.

typedef enum *_pwm_force_signal* pwm_force_signal_t
PWM output options when a FORCE_OUT signal is asserted.

typedef enum *_pwm_chnl_pair_operation* pwm_chnl_pair_operation_t
Options available for the PWM A & B pair operation.

typedef enum *_pwm_register_reload* pwm_register_reload_t
Options available on how to load the buffered-registers with new values.

typedef enum *_pwm_fault_recovery_mode* pwm_fault_recovery_mode_t
Options available on how to re-enable the PWM output when recovering from a fault.

typedef enum *_pwm_interrupt_enable* pwm_interrupt_enable_t
List of PWM interrupt options.

typedef enum *_pwm_status_flags* pwm_status_flags_t
List of PWM status flags.

typedef enum *_pwm_dma_enable* pwm_dma_enable_t
List of PWM DMA options.

typedef enum *_pwm_dma_source_select* pwm_dma_source_select_t

List of PWM capture DMA enable source select.

typedef enum *_pwm_watermark_control* pwm_watermark_control_t

PWM FIFO Watermark AND Control.

typedef enum *_pwm_mode* pwm_mode_t

PWM operation mode.

typedef enum *_pwm_level_select* pwm_level_select_t

PWM output pulse mode, high-true or low-true.

typedef enum *_pwm_fault_state* pwm_fault_state_t

PWM output fault status.

typedef enum *_pwm_reload_source_select* pwm_reload_source_select_t

PWM reload source select.

typedef enum *_pwm_fault_clear* pwm_fault_clear_t

PWM fault clearing options.

typedef enum *_pwm_module_control* pwm_module_control_t

Options for submodule master control operation.

typedef struct *_pwm_signal_param* pwm_signal_param_t

Structure for the user to define the PWM signal characteristics.

typedef struct *_pwm_config* pwm_config_t

PWM config structure.

This structure holds the configuration settings for the PWM peripheral. To initialize this structure to reasonable defaults, call the *PWM_GetDefaultConfig()* function and pass a pointer to your config structure instance.

The config struct can be made const so it resides in flash

typedef struct *_pwm_fault_input_filter_param* pwm_fault_input_filter_param_t

Structure for the user to configure the fault input filter.

typedef struct *_pwm_fault_param* pwm_fault_param_t

Structure is used to hold the parameters to configure a PWM fault.

typedef struct *_pwm_input_capture_param* pwm_input_capture_param_t

Structure is used to hold parameters to configure the capture capability of a signal pin.

void PWM_SetupInputCapture(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_channels_t* pwmChannel, const *pwm_input_capture_param_t* *inputCaptureParams)

Sets up the PWM input capture.

Each PWM submodule has 3 pins that can be configured for use as input capture pins. This function sets up the capture parameters for each pin and enables the pin for input capture operation.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- pwmChannel – Channel in the submodule to setup
- inputCaptureParams – Parameters passed in to set up the input pin

status_t PWM_GetInputCaptureValue(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_channels_t* pwmChannel, uint8_t captureIndex, uint16_t *captureValue)

Read the capture value.

This function reads the capture value stored in channel's capture value register. It should be called when a valid edge is detected on the input capture pin(related capture flag is set). The capture circuit has two input capture registers per channel for first edge and second edge capture.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- pwmChannel – PWM channel to read from (PWM A, PWM B, or PWM X)
- captureIndex – Capture register to read (0 for first edge capture, 1 for second edge capture)

Returns

Returns kStatus_InvalidArgument if pwmChannel does not support capture feature; kStatus_Success otherwise

void PWM_SetupFaultInputFilter(PWM_Type *base, const *pwm_fault_input_filter_param_t* *faultInputFilterParams)

Sets up the PWM fault channel 0 input filter.

Parameters

- base – PWM peripheral base address
- faultInputFilterParams – Parameters passed in to set up the fault input filter.

void PWM_SetupFaultInputFilterExt(PWM_Type *base, *pwm_fault_channels_t* faultChannel, const *pwm_fault_input_filter_param_t* *faultInputFilterParams)

Sets up the PWM fault input filter.

Parameters

- base – PWM peripheral base address
- faultChannel – PWM fault channel to configure.
- faultInputFilterParams – Parameters passed in to set up the fault input filter.

void PWM_SetupFaults(PWM_Type *base, *pwm_fault_input_t* faultNum, const *pwm_fault_param_t* *faultParams)

Sets up the PWM fault channel 0 protection.

Parameters

- base – PWM peripheral base address
- faultNum – PWM fault to configure.
- faultParams – Pointer to the PWM fault config structure

void PWM_SetupFaultsExt(PWM_Type *base, *pwm_fault_channels_t* faultChannel, *pwm_fault_input_t* faultNum, const *pwm_fault_param_t* *faultParams)

Sets up the PWM fault protection.

Parameters

- base – PWM peripheral base address
- faultChannel – PWM fault channel to configure.
- faultNum – PWM fault to configure.
- faultParams – Pointer to the PWM fault config structure

void PWM_FaultDefaultConfig(*pwm_fault_param_t* *config)

Fill in the PWM fault config struct with the default settings.

The default values are:

```
config->faultClearingMode = kPWM_Automatic;
config->faultLevel = false;
config->enableCombinationalPath = true;
config->recoverMode = kPWM_NoRecovery;
```

Parameters

- config – Pointer to user's PWM fault config structure.

void PWM_SetupForceSignal(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_channels_t* pwmChannel, *pwm_force_signal_t* mode)

Selects the signal to output on a PWM pin when a FORCE_OUT signal is asserted.

The user specifies which channel to configure by supplying the submodule number and whether to modify PWM A or PWM B within that submodule.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- pwmChannel – Channel to configure
- mode – Signal to output when a FORCE_OUT is triggered

static inline void PWM_EnableLocalForce(PWM_Type *base, *pwm_submodule_t* subModule)

Enables local software force initialization on a PWM submodule.

This function performs a software-controlled initialization, causes a FORCE_OUT event which latches all double-buffered fields (DTSRCSEL, MCTRL[IPOL], SWCOUT) into their active registers and, if MCTRL[LDOK] is set, also triggers a register reload.

Call this function after updating the desired buffered registers (e.g. after *PWM_SetupForceSignal()*) to apply the new values synchronously.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to enable local force on

void PWM_UpdateCurrentPolarity(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_chnl_pair_operation_t* polarity)

Updates the current polarity (MCTRL[IPOL]) for a PWM submodule.

MCTRL[IPOL] is a double-buffered field. This function only writes the shadow register; the value does NOT take effect until a FORCE_OUT event occurs. Call *PWM_EnableLocalForce()* after this function to apply all pending changes atomically in one FORCE_OUT event.

Only meaningful when the submodule operates in complementary mode (CTRL2[INDEP] = 0).

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- polarity – kPWM_ComplementaryPwmA: PWM23 (VAL2/VAL3) drives the complementary pair kPWM_ComplementaryPwmB: PWM45 (VAL4/VAL5) drives the complementary pair

static inline void PWM_SetVALxValue(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_value_register_t* valueRegister, uint16_t value)

Set the PWM VALx registers.

This function allows the user to write value into VAL registers directly. And it will destroying the PWM clock period set by the *PWM_SetupPwm()*/PWM_SetupPwmPhaseShift() functions. Due to VALx registers are bufferd, the new value will not active uless call *PWM_SetPwmLdok()* and the reload point is reached.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- valueRegister – VALx register that will be writen new value
- value – Value that will been write into VALx register

static inline uint16_t PWM_GetVALxValue(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_value_register_t* valueRegister)

Get the PWM VALx registers.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- valueRegister – VALx register that will be read value

Returns

The VALx register value

static inline void PWM_OutputTriggerEnable(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_value_register_t* valueRegister, bool activate)

Enables or disables the PWM output trigger.

This function allows the user to enable or disable the PWM trigger. The PWM has 2 triggers. Trigger 0 is activated when the counter matches VAL 0, VAL 2, or VAL 4 register. Trigger 1 is activated when the counter matches VAL 1, VAL 3, or VAL 5 register.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- valueRegister – Value register that will activate the trigger
- activate – true: Enable the trigger; false: Disable the trigger

static inline void PWM_ActivateOutputTrigger(PWM_Type *base, *pwm_submodule_t* subModule, uint16_t valueRegisterMask)

Enables the PWM output trigger.

This function allows the user to enable one or more (VAL0-5) PWM trigger.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- valueRegisterMask – Value register mask that will activate one or more (VAL0-5) trigger enumeration *_pwm_value_register_mask*

static inline void PWM_DeactivateOutputTrigger(PWM_Type *base, *pwm_submodule_t* subModule, uint16_t valueRegisterMask)

Disables the PWM output trigger.

This function allows the user to disables one or more (VAL0-5) PWM trigger.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- valueRegisterMask – Value register mask that will Deactivate one or more (VAL0-5) trigger enumeration *_pwm_value_register_mask*

static inline void PWM_SetupSwCtrlOut(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_channels_t* pwmChannel, bool value)

Sets the software control output for a pin to high or low.

The user specifies which channel to modify by supplying the submodule number and whether to modify PWM A or PWM B within that submodule.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- pwmChannel – Channel to configure
- value – true: Supply a logic 1, false: Supply a logic 0.

static inline void PWM_SetPwmLdok(PWM_Type *base, uint8_t subModulesToUpdate, bool value)

Sets or clears the PWM LDOK bit on a single or multiple submodules.

Set LDOK bit to load buffered values into CTRL[PRSC] and the INIT, FRACVAL and VAL registers. The values are loaded immediately if kPWM_ReloadImmediate option was choosen during config. Else the values are loaded at the next PWM reload point. This function can issue the load command to multiple submodules at the same time.

Parameters

- base – PWM peripheral base address
- subModulesToUpdate – PWM submodules to update with buffered values. This is a logical OR of members of the enumeration *pwm_module_control_t*
- value – true: Set LDOK bit for the submodule list; false: Clear LDOK bit

static inline void PWM_SetPwmFaultState(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_channels_t* pwmChannel, *pwm_fault_state_t* faultState)

Set PWM output fault status.

These bits determine the fault state for the PWM_A output in fault conditions and STOP mode. It may also define the output state in WAIT and DEBUG modes depending on the settings of CTRL2[WAITEN] and CTRL2[DBGEN]. This function can update PWM output fault status.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- pwmChannel – Channel to configure
- faultState – PWM output fault status

static inline void PWM_SetupFaultDisableMap(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_channels_t* pwmChannel, *pwm_fault_channels_t* pwm_fault_channels, uint16_t value)

Set PWM fault disable mapping.

Each of the four bits of this read/write field is one-to-one associated with the four FAULTx inputs of fault channel 0/1. The PWM output will be turned off if there is a logic 1 on an FAULTx input and a 1 in the corresponding bit of this field. A reset sets all bits in this field.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- pwmChannel – PWM channel to configure
- pwm_fault_channels – PWM fault channel to configure
- value – Fault disable mapping mask value enumeration *pwm_fault_disable_t*

static inline void PWM_OutputEnable(PWM_Type *base, *pwm_channels_t* pwmChannel, *pwm_submodule_t* subModule)

Set PWM output enable.

This feature allows the user to enable the PWM Output. Recommend to invoke this API after PWM and fault configuration. But invoke this API before configure MCTRL register is okay, such as set LDOK or start timer.

Parameters

- base – PWM peripheral base address
- pwmChannel – PWM channel to configure
- subModule – PWM submodule to configure

static inline void PWM_OutputDisable(PWM_Type *base, *pwm_channels_t* pwmChannel, *pwm_submodule_t* subModule)

Set PWM output disable.

This feature allows the user to disable the PWM output. Recommend to invoke this API after PWM and fault configuration. But invoke this API before configure MCTRL register is okay, such as set LDOK or start timer.

Parameters

- base – PWM peripheral base address
- pwmChannel – PWM channel to configure

- subModule – PWM submodule to configure

uint8_t PWM_GetPwmChannelState(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_channels_t* pwmChannel)

Get the dutycycle value.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- pwmChannel – PWM channel to configure

Returns

Current channel dutycycle value.

status_t PWM_SetOutputToIdle(PWM_Type *base, *pwm_channels_t* pwmChannel, *pwm_submodule_t* subModule, bool idleStatus)

Set PWM output in idle status (high or low).

Note: This API should call after *PWM_SetupPwm()* APIs, and PWMX submodule is not supported.

Parameters

- base – PWM peripheral base address
- pwmChannel – PWM channel to configure
- subModule – PWM submodule to configure
- idleStatus – True: PWM output is high in idle status; false: PWM output is low in idle status.

Returns

kStatus_Fail if there was error setting up the signal; kStatus_Success if set output idle success

void PWM_SetClockMode(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_clock_prescale_t* prescaler)

Set the pwm submodule prescaler.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- prescaler – Set prescaler value

void PWM_SetPwmForceOutputToZero(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_channels_t* pwmChannel, bool forcetozero)

This function enables-disables the forcing of the output of a given eFlexPwm channel to logic 0.

Parameters

- base – PWM peripheral base address
- pwmChannel – PWM channel to configure
- subModule – PWM submodule to configure
- forcetozero – True: Enable the pwm force output to zero; False: Disable the pwm output resumes normal function.

void PWM_SetChannelOutput(PWM_Type *base, *pwm_submodule_t* subModule, *pwm_channels_t* pwmChannel, *pwm_output_state_t* outputstate)

This function set the output state of the PWM pin as requested for the current cycle.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- pwmChannel – PWM channel to configure
- outputstate – Set pwm output state, see *pwm_output_state_t*.

status_t PWM_SetPhaseDelay(PWM_Type *base, *pwm_channels_t* pwmChannel, *pwm_submodule_t* subModule, uint16_t delayCycles)

This function set the phase delay from the master sync signal of submodule 0.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- pwmChannel – PWM channel to configure
- delayCycles – Number of cycles delayed from submodule 0.

Returns

kStatus_Fail if the number of delay cycles is set larger than the period defined in submodule 0; kStatus_Success if set phase delay success

static inline void PWM_SetFilterSampleCount(PWM_Type *base, *pwm_channels_t* pwmChannel, *pwm_submodule_t* subModule, uint8_t filterSampleCount)

This function set the number of consecutive samples that must agree prior to the input filter.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- pwmChannel – PWM channel to configure
- filterSampleCount – Number of consecutive samples.

static inline void PWM_SetFilterSamplePeriod(PWM_Type *base, *pwm_channels_t* pwmChannel, *pwm_submodule_t* subModule, uint8_t filterSamplePeriod)

This function set the sampling period of the fault pin input filter.

Parameters

- base – PWM peripheral base address
- subModule – PWM submodule to configure
- pwmChannel – PWM channel to configure
- filterSamplePeriod – Sampling period of input filter.

PWM_SUBMODULE_SWCONTROL_WIDTH

Number of bits per submodule for software output control

PWM_SUBMODULE_CHANNEL

Submodule channels include PWMA, PWMB, PWMX.

struct _pwm_signal_param

#include <fsl_pwm.h> Structure for the user to define the PWM signal characteristics.

Public Members

pwm_channels_t pwmChannel

PWM channel being configured; PWM A or PWM B

uint8_t dutyCyclePercent

PWM pulse width, value should be between 0 to 100 0=inactive signal(0% duty cycle)... 100=always active signal (100% duty cycle)

pwm_level_select_t level

PWM output active level select

uint16_t deadtimeValue

The deadtime value; only used if channel pair is operating in complementary mode

pwm_fault_state_t faultState

PWM output fault status

bool pwmchannelenable

Enable PWM output

struct _pwm_config

#include <fsl_pwm.h> PWM config structure.

This structure holds the configuration settings for the PWM peripheral. To initialize this structure to reasonable defaults, call the *PWM_GetDefaultConfig()* function and pass a pointer to your config structure instance.

The config struct can be made const so it resides in flash

Public Members

bool enableDebugMode

true: PWM continues to run in debug mode; false: PWM is paused in debug mode

pwm_init_source_t initializationControl

Option to initialize the counter

pwm_clock_source_t clockSource

Clock source for the counter

pwm_clock_prescale_t prescale

Pre-scaler to divide down the clock

pwm_chnl_pair_operation_t pairOperation

Channel pair in indepedent or complementary mode

pwm_register_reload_t reloadLogic

PWM Reload logic setup

pwm_reload_source_select_t reloadSelect

Reload source select

pwm_load_frequency_t reloadFrequency

Specifies when to reload, used when user's choice is not immediate reload

pwm_force_output_trigger_t forceTrigger

Specify which signal will trigger a FORCE_OUT

struct __pwm_fault_input_filter_param

#include <fsl_pwm.h> Structure for the user to configure the fault input filter.

Public Members

uint8_t faultFilterCount

Fault filter count

uint8_t faultFilterPeriod

Fault filter period;value of 0 will bypass the filter

bool faultGlitchStretch

Fault Glitch Stretch Enable: A logic 1 means that input fault signals will be stretched to at least 2 IPBus clock cycles

struct __pwm_fault_param

#include <fsl_pwm.h> Structure is used to hold the parameters to configure a PWM fault.

Public Members

pwm_fault_clear_t faultClearingMode

Fault clearing mode to use

bool faultLevel

true: Logic 1 indicates fault; false: Logic 0 indicates fault

bool enableCombinationalPath

true: Combinational Path from fault input is enabled; false: No combination path is available

pwm_fault_recovery_mode_t recoverMode

Specify when to re-enable the PWM output

struct __pwm__input__capture__param

#include <fsl_pwm.h> Structure is used to hold parameters to configure the capture capability of a signal pin.

Public Members

bool captureInputSel

true: Use the edge counter signal as source false: Use the raw input signal from the pin as source

uint8_t edgeCompareValue

Compare value, used only if edge counter is used as source

pwm_input_capture_edge_t edge0

Specify which edge causes a capture for input circuitry 0

pwm_input_capture_edge_t edge1

Specify which edge causes a capture for input circuitry 1

bool enableOneShotCapture

true: Use one-shot capture mode; false: Use free-running capture mode

uint8_t fifoWatermark

Watermark level for capture FIFO. The capture flags in the status register will set if the word count in the FIFO is greater than this watermark level

2.68 RTC: Real Time Clock

void RTC_Init(RTC_Type *base, const *rtc_config_t* *config)

Ungates the RTC clock and configures the peripheral for basic operation.

This function issues a software reset if the timer invalid flag is set.

Note: This API should be called at the beginning of the application using the RTC driver.

Parameters

- base – RTC peripheral base address
- config – Pointer to the user's RTC configuration structure.

static inline void RTC_Deinit(RTC_Type *base)

Stops the timer and gate the RTC clock.

Parameters

- base – RTC peripheral base address

void RTC_GetDefaultConfig(*rtc_config_t* *config)

Fills in the RTC config struct with the default settings.

The default values are as follows.

```
config->clockOutput = false;
config->wakeupSelect = false;
config->updateMode = false;
config->supervisorAccess = false;
config->compensationInterval = 0;
config->compensationTime = 0;
```

Parameters

- config – Pointer to the user's RTC configuration structure.

status_t RTC_SetDatetime(RTC_Type *base, const *rtc_datetime_t* *datetime)

Sets the RTC date and time according to the given time structure.

The RTC counter must be stopped prior to calling this function because writes to the RTC seconds register fail if the RTC counter is running.

Parameters

- base – RTC peripheral base address
- datetime – Pointer to the structure where the date and time details are stored.

Returns

kStatus_Success: Success in setting the time and starting the RTC kStatus_InvalidArgument: Error because the datetime format is incorrect

void RTC_GetDatetime(RTC_Type *base, *rtc_datetime_t* *datetime)

Gets the RTC time and stores it in the given time structure.

Parameters

- base – RTC peripheral base address
- datetime – Pointer to the structure where the date and time details are stored.

status_t RTC_SetAlarm(RTC_Type *base, const *rtc_datetime_t* *alarmTime)

Sets the RTC alarm time.

The function checks whether the specified alarm time is greater than the present time. If not, the function does not set the alarm and returns an error.

Parameters

- base – RTC peripheral base address
- alarmTime – Pointer to the structure where the alarm time is stored.

Returns

kStatus_Success: success in setting the RTC alarm kStatus_InvalidArgument: Error because the alarm datetime format is incorrect kStatus_Fail: Error because the alarm time has already passed

void RTC_GetAlarm(RTC_Type *base, *rtc_datetime_t* *datetime)

Returns the RTC alarm time.

Parameters

- base – RTC peripheral base address

- datetime – Pointer to the structure where the alarm date and time details are stored.

void RTC_EnableInterrupts(RTC_Type *base, uint32_t mask)

Enables the selected RTC interrupts.

Parameters

- base – RTC peripheral base address
- mask – The interrupts to enable. This is a logical OR of members of the enumeration *rtc_interrupt_enable_t*

void RTC_DisableInterrupts(RTC_Type *base, uint32_t mask)

Disables the selected RTC interrupts.

Parameters

- base – RTC peripheral base address
- mask – The interrupts to enable. This is a logical OR of members of the enumeration *rtc_interrupt_enable_t*

uint32_t RTC_GetEnabledInterrupts(RTC_Type *base)

Gets the enabled RTC interrupts.

Parameters

- base – RTC peripheral base address

Returns

The enabled interrupts. This is the logical OR of members of the enumeration *rtc_interrupt_enable_t*

uint32_t RTC_GetStatusFlags(RTC_Type *base)

Gets the RTC status flags.

Parameters

- base – RTC peripheral base address

Returns

The status flags. This is the logical OR of members of the enumeration *rtc_status_flags_t*

void RTC_ClearStatusFlags(RTC_Type *base, uint32_t mask)

Clears the RTC status flags.

Parameters

- base – RTC peripheral base address
- mask – The status flags to clear. This is a logical OR of members of the enumeration *rtc_status_flags_t*

static inline void RTC_EnableLPOClock(RTC_Type *base, bool enable)

Enable/Disable RTC 1kHz LPO clock.

Note: After setting this bit, RTC prescaler increments using the LPO 1kHz clock and not the RTC 32kHz crystal clock.

Parameters

- base – RTC peripheral base address
- enable – Enable/Disable RTC 1kHz LPO clock

static inline void RTC_StartTimer(RTC_Type *base)

Starts the RTC time counter.

After calling this function, the timer counter increments once a second provided SR[TOF] or SR[TIF] are not set.

Parameters

- base – RTC peripheral base address

static inline void RTC_StopTimer(RTC_Type *base)

Stops the RTC time counter.

RTC's seconds register can be written to only when the timer is stopped.

Parameters

- base – RTC peripheral base address

void RTC_GetMonotonicCounter(RTC_Type *base, uint64_t *counter)

Reads the values of the Monotonic Counter High and Monotonic Counter Low and returns them as a single value.

Parameters

- base – RTC peripheral base address
- counter – Pointer to variable where the value is stored.

void RTC_SetMonotonicCounter(RTC_Type *base, uint64_t counter)

Writes values Monotonic Counter High and Monotonic Counter Low by decomposing the given single value. The Monotonic Overflow Flag in RTC_SR is cleared due to the API.

Parameters

- base – RTC peripheral base address
- counter – Counter value

status_t RTC_IncrementMonotonicCounter(RTC_Type *base)

Increments the Monotonic Counter by one.

Increments the Monotonic Counter (registers RTC_MCLR and RTC_MCHR accordingly) by setting the monotonic counter enable (MER[MCE]) and then writing to the RTC_MCLR register. A write to the monotonic counter low that causes it to overflow also increments the monotonic counter high.

Parameters

- base – RTC peripheral base address

Returns

kStatus_Success: success kStatus_Fail: error occurred, either time invalid or monotonic overflow flag was found

FSL_RTC_DRIVER_VERSION

Version 2.4.0

enum _rtc_interrupt_enable

List of RTC interrupts.

Values:

enumerator kRTC_TimeInvalidInterruptEnable

Time invalid interrupt.

enumerator kRTC_TimeOverflowInterruptEnable
Time overflow interrupt.

enumerator kRTC_AlarmInterruptEnable
Alarm interrupt.

enumerator kRTC_MonotonicOverflowInterruptEnable
Monotonic Overflow Interrupt Enable

enumerator kRTC_SecondsInterruptEnable
Seconds interrupt.

enumerator kRTC_TestModeInterruptEnable

enumerator kRTC_FlashSecurityInterruptEnable

enumerator kRTC_TamperPinInterruptEnable

enumerator kRTC_SecurityModuleInterruptEnable

enumerator kRTC_LossOfClockInterruptEnable

enum _rtc_status_flags
List of RTC flags.
Values:

enumerator kRTC_TimeInvalidFlag
Time invalid flag

enumerator kRTC_TimeOverflowFlag
Time overflow flag

enumerator kRTC_AlarmFlag
Alarm flag

enumerator kRTC_MonotonicOverflowFlag
Monotonic Overflow Flag

enumerator kRTC_TamperInterruptDetectFlag
Tamper interrupt detect flag

enumerator kRTC_TestModeFlag

enumerator kRTC_FlashSecurityFlag

enumerator kRTC_TamperPinFlag

enumerator kRTC_SecurityTamperFlag

enumerator kRTC_LossOfClockTamperFlag

enum _rtc_osc_cap_load

List of RTC Oscillator capacitor load settings.

Values:

enumerator kRTC_Capacitor_2p

2 pF capacitor load

enumerator kRTC_Capacitor_4p

4 pF capacitor load

enumerator kRTC_Capacitor_8p

8 pF capacitor load

enumerator kRTC_Capacitor_16p

16 pF capacitor load

enum _rtc_timer_seconds_interrupt_frequency

List of RTC Timer Seconds Interrupt Frequencies.

Values:

enumerator kRTC_TimerSecondsFrequency1Hz

Timer seconds frequency is 1Hz

enumerator kRTC_TimerSecondsFrequency2Hz

Timer seconds frequency is 2Hz

enumerator kRTC_TimerSecondsFrequency4Hz

Timer seconds frequency is 4Hz

enumerator kRTC_TimerSecondsFrequency8Hz

Timer seconds frequency is 8Hz

enumerator kRTC_TimerSecondsFrequency16Hz

Timer seconds frequency is 16Hz

enumerator kRTC_TimerSecondsFrequency32Hz

Timer seconds frequency is 32Hz

enumerator kRTC_TimerSecondsFrequency64Hz

Timer seconds frequency is 64Hz

enumerator kRTC_TimerSecondsFrequency128Hz

Timer seconds frequency is 128Hz

typedef enum *_rtc_interrupt_enable* rtc_interrupt_enable_t

List of RTC interrupts.

typedef enum *_rtc_status_flags* rtc_status_flags_t

List of RTC flags.

typedef enum *_rtc_osc_cap_load* rtc_osc_cap_load_t

List of RTC Oscillator capacitor load settings.

typedef enum *_rtc_timer_seconds_interrupt_frequency* rtc_timer_seconds_interrupt_frequency_t

List of RTC Timer Seconds Interrupt Frequencies.

typedef struct *_rtc_datetime* rtc_datetime_t

Structure is used to hold the date and time.

typedef struct *_rtc_pin_config* rtc_pin_config_t

RTC pin config structure.

typedef struct *_rtc_config* rtc_config_t

RTC config structure.

This structure holds the configuration settings for the RTC peripheral. To initialize this structure to reasonable defaults, call the *RTC_GetDefaultConfig()* function and pass a pointer to your config structure instance.

The config struct can be made const so it resides in flash

static inline uint32_t RTC_GetTamperTimeSeconds(RTC_Type *base)

Get the RTC tamper time seconds.

Parameters

- base – RTC peripheral base address

static inline void RTC_SetOscCapLoad(RTC_Type *base, uint32_t capLoad)

This function sets the specified capacitor configuration for the RTC oscillator.

Parameters

- base – RTC peripheral base address
- capLoad – Oscillator loads to enable. This is a logical OR of members of the enumeration *rtc_osc_cap_load_t*

static inline void RTC_Reset(RTC_Type *base)

Performs a software reset on the RTC module.

This resets all RTC registers except for the SWR bit and the RTC_WAR and RTC_RAR registers. The SWR bit is cleared by software explicitly clearing it.

Parameters

- base – RTC peripheral base address

static inline void RTC_EnableWakeUpPin(RTC_Type *base, bool enable)

Enables or disables the RTC Wakeup Pin Operation.

This function enable or disable RTC Wakeup Pin. The wakeup pin is optional and not available on all devices.

Parameters

- base – RTC_Type base pointer.
- enable – true to enable, false to disable.

static inline void RTC_EnableClockOutput(RTC_Type *base, bool enable)

Enables or disables the RTC 32 kHz clock output.

This function enables or disables the RTC 32 kHz clock output.

Parameters

- base – RTC_Type base pointer.
- enable – true to enable, false to disable.

void RTC_SetTimerSecondsInterruptFrequency(RTC_Type *base, *rtc_timer_seconds_interrupt_frequency_t* freq)

Sets the RTC timer seconds interrupt frequency.

This function sets the RTC timer seconds interrupt frequency.

Parameters

- base – RTC peripheral base address
- freq – The timer seconds interrupt frequency. This is a member of the enumeration *rtc_timer_seconds_interrupt_frequency_t*

struct __rtc_datetime

#include <fsl_rtc.h> Structure is used to hold the date and time.

Public Members

uint16_t year

Range from 1970 to 2099.

uint8_t month

Range from 1 to 12.

uint8_t day

Range from 1 to 31 (depending on month).

uint8_t hour

Range from 0 to 23.

uint8_t minute

Range from 0 to 59.

uint8_t second

Range from 0 to 59.

struct __rtc_pin_config

#include <fsl_rtc.h> RTC pin config structure.

Public Members

bool inputLogic

true: Tamper pin input data is logic one. false: Tamper pin input data is logic zero.

bool pinActiveLow

true: Tamper pin is active low. false: Tamper pin is active high.

bool filterEnable

true: Input filter is enabled on the tamper pin. false: Input filter is disabled on the tamper pin.

bool pullSelectNegate

true: Tamper pin pull resistor direction will negate the tamper pin. false: Tamper pin pull resistor direction will assert the tamper pin.

bool pullEnable

true: Pull resistor is enabled on tamper pin. false: Pull resistor is disabled on tamper pin.

struct _rtc_config

#include <fsl_rtc.h> RTC config structure.

This structure holds the configuration settings for the RTC peripheral. To initialize this structure to reasonable defaults, call the *RTC_GetDefaultConfig()* function and pass a pointer to your config structure instance.

The config struct can be made const so it resides in flash

Public Members

bool clockOutput

true: The 32 kHz clock is not output to other peripherals; false: The 32 kHz clock is output to other peripherals

bool wakeupSelect

true: Wakeup pin outputs the 32 KHz clock; false:Wakeup pin used to wakeup the chip

bool updateMode

true: Registers can be written even when locked under certain conditions, false: No writes allowed when registers are locked

bool supervisorAccess

true: Non-supervisor accesses are allowed; false: Non-supervisor accesses are not supported

uint32_t compensationInterval

Compensation interval that is written to the CIR field in RTC TCR Register

uint32_t compensationTime

Compensation time that is written to the TCR field in RTC TCR Register

2.69 SLCD: Segment LCD Driver

void SLCD_Init(LCD_Type *base, *slcd_config_t* *configure)

Initializes the SLCD, ungates the module clock, initializes the power setting, enables all used plane pins, and sets with interrupt and work mode with the configuration.

Parameters

- base – SLCD peripheral base address.
- configure – SLCD configuration pointer. For the configuration structure, many parameters have the default setting and the SLCD_Getdefaultconfig() is provided to get them. Use it verified for their applications. The others have no default settings, such as "clkConfig", and must be provided by the application before calling the *SLCD_Init()* API.

void SLCD_Deinit(LCD_Type *base)

Deinitializes the SLCD module, gates the module clock, disables an interrupt, and displays the SLCD.

Parameters

- base – SLCD peripheral base address.

void SLCD_GetDefaultConfig(*slcd_config_t* *configure)

Gets the SLCD default configuration structure. The purpose of this API is to get default parameters of the configuration structure for the *SLCD_Init()*. Use these initialized parameters unchanged in *SLCD_Init()* or modify fields of the structure before the calling *SLCD_Init()*. All default parameters of the configure structuration are listed.

```
config.displayMode         = kSLCD_NormalMode;
config.powerSupply         = kSLCD_InternalVll3UseChargePump;
config.voltageTrim         = kSLCD_RegulatedVolatgeTrim00;
config.lowPowerBehavior    = kSLCD_EnabledInWaitStop;
config.interruptSrc        = 0;
config.faultConfig         = NULL;
config.frameFreqIntEnable =  false;
```

Parameters

- configure – The SLCD configuration structure pointer.

static inline void SLCD_StartDisplay(LCD_Type *base)

Enables the SLCD controller, starts generation, and displays the front plane and back plane waveform.

Parameters

- base – SLCD peripheral base address.

static inline void SLCD_StopDisplay(LCD_Type *base)

Stops the SLCD controller. There is no waveform generator and all enabled pins only output a low value.

Parameters

- base – SLCD peripheral base address.

void SLCD_StartBlinkMode(LCD_Type *base, *slcd_blink_mode_t* mode, *slcd_blink_rate_t* rate)

Starts the SLCD blink mode.

Parameters

- base – SLCD peripheral base address.
- mode – SLCD blink mode.
- rate – SLCD blink rate.

static inline void SLCD_StopBlinkMode(LCD_Type *base)

Stops the SLCD blink mode.

Parameters

- base – SLCD peripheral base address.

static inline void SLCD_SetBackPlanePhase(LCD_Type *base, uint32_t pinIndx, *slcd_phase_type_t* phase)

Sets the SLCD back plane pin phase.

This function sets the SLCD back plane pin phase. "kSLCD_PhaseXActivate" setting means the phase X is active for the back plane pin. "kSLCD_NoPhaseActivate" setting means there is no phase active for the back plane pin. For example, set the back plane pin 20 for phase A.

```
SLCD_SetBackPlanePhase(LCD, 20, kSLCD_PhaseAActivate);
```

Parameters

- base – SLCD peripheral base address.
- pinIndx – SLCD back plane pin index. Range from 0 to (LCD_WFOVERLAY_WFACCESS32BIT_WF_COUNT * 4 - 1).
- phase – The phase activates for the back plane pin.

static inline void SLCD_SetFrontPlaneSegments(LCD_Type *base, uint32_t pinIndx, uint8_t operation)

Sets the SLCD front plane segment operation for a front plane pin.

This function sets the SLCD front plane segment on or off operation. Each bit turns on or off the segments associated with the front plane pin in the following pattern: HGFEDCBA (most significant bit controls segment H and least significant bit controls segment A). For example, turn on the front plane pin 20 for phase B and phase C.

```
SLCD_SetFrontPlaneSegments(LCD, 20, (kSLCD_PhaseBActivate | kSLCD_PhaseCActivate));
```

Parameters

- base – SLCD peripheral base address.
- pinIndx – SLCD front plane pin index. Range from 0 to (LCD_WFOVERLAY_WFACCESS32BIT_WF_COUNT * 4 - 1).
- operation – The operation for the segment on the front plane pin. This is a logical OR of the enumeration :: slcd_phase_type_t.

static inline void SLCD_SetFrontPlaneOnePhase(LCD_Type *base, uint32_t pinIndx, *slcd_phase_index_t* phaseIndx, bool enable)

Sets one SLCD front plane pin for one phase.

This function can be used to set one phase on or off for the front plane pin. It can be call many times to set the plane pin for different phase indexes. For example, turn on the front plane pin 20 for phase B and phase C.

```
SLCD_SetFrontPlaneOnePhase(LCD, 20, kSLCD_PhaseBIndex, true);
SLCD_SetFrontPlaneOnePhase(LCD, 20, kSLCD_PhaseCIndex, true);
```

Parameters

- base – SLCD peripheral base address.
- pinIndx – SLCD front plane pin index. Range from 0 to (LCD_WFOVERLAY_WFACCESS32BIT_WF_COUNT * 4 - 1).
- phaseIndx – The phase bit index *slcd_phase_index_t*.
- enable – True to turn on the segment for phaseIndx phase false to turn off the segment for phaseIndx phase.

static inline void SLCD_EnablePadSafeState(LCD_Type *base, bool enable)

Enables/disables the SLCD pad safe state.

Forces the safe state on the LCD pad controls. All LCD front plane and backplane functions are disabled.

Parameters

- base – SLCD peripheral base address.
- enable – True enable, false disable.

static inline uint32_t SLCD_GetFaultDetectCounter(LCD_Type *base)

Gets the SLCD fault detect counter.

This function gets the number of samples inside the fault detection sample window.

Parameters

- base – SLCD peripheral base address.

Returns

The fault detect counter. The maximum return value is 255. If the maximum 255 returns, the overflow may happen. Reconfigure the fault detect sample window and fault detect clock prescaler for proper sampling.

void SLCD_EnableInterrupts(LCD_Type *base, uint32_t mask)

Enables the SLCD interrupt. For example, to enable fault detect complete interrupt and frame frequency interrupt, for FSL_FEATURE_SLCD_HAS_FRAME_FREQUENCY_INTERRUPT enabled case, do the following.

```
SLCD_EnableInterrupts(LCD,kSLCD_FaultDetectCompleteInterrupt | kSLCD_FrameFreqInterrupt);
```

Parameters

- base – SLCD peripheral base address.
- mask – SLCD interrupts to enable. This is a logical OR of the enumeration :: slcd_interrupt_enable_t.

void SLCD_DisableInterrupts(LCD_Type *base, uint32_t mask)

Disables the SLCD interrupt. For example, to disable fault detect complete interrupt and frame frequency interrupt, for FSL_FEATURE_SLCD_HAS_FRAME_FREQUENCY_INTERRUPT enabled case, do the following.

```
SLCD_DisableInterrupts(LCD,kSLCD_FaultDetectCompleteInterrupt | kSLCD_FrameFreqInterrupt);
```

Parameters

- base – SLCD peripheral base address.
- mask – SLCD interrupts to disable. This is a logical OR of the enumeration :: slcd_interrupt_enable_t.

uint32_t SLCD_GetInterruptStatus(LCD_Type *base)

Gets the SLCD interrupt status flag.

Parameters

- base – SLCD peripheral base address.

Returns

The event status of the interrupt source. This is the logical OR of members of the enumeration :: slcd_interrupt_enable_t.

void SLCD_ClearInterruptStatus(LCD_Type *base, uint32_t mask)

Clears the SLCD interrupt events status flag.

Parameters

- base – SLCD peripheral base address.
- mask – SLCD interrupt source to be cleared. This is the logical OR of members of the enumeration :: slcd_interrupt_enable_t.

FSL_SLCD_DRIVER_VERSION

SLCD driver version.

enum _slcd_clock_prescaler

SLCD clock prescaler to generate frame frequency.

Values:

enumerator kSLCD_ClkPrescaler00

Prescaler 0.

enumerator kSLCD_ClkPrescaler01

Prescaler 1.

enumerator kSLCD_ClkPrescaler02

Prescaler 2.

enumerator kSLCD_ClkPrescaler03

Prescaler 3.

enumerator kSLCD_ClkPrescaler04

Prescaler 4.

enumerator kSLCD_ClkPrescaler05

Prescaler 5.

enumerator kSLCD_ClkPrescaler06

Prescaler 6.

enumerator kSLCD_ClkPrescaler07
Prescaler 7.

enum _slcd_regulated_voltage_trim
SLCD regulated voltage trim parameter, be used to meet the desired contrast.
Values:

enumerator kSLCD_VolatgeTrimNo
No voltage trim.

enumerator kSLCD_VolatgeTrimIncrease50mV
Increase the voltage by 50 mV.

enumerator kSLCD_VolatgeTrimIncrease100mV
Increase the voltage by 100 mV.

enumerator kSLCD_VolatgeTrimIncrease150mV
Increase the voltage by 150 mV.

enumerator kSLCD_VolatgeTrimIncrease200mV
Increase the voltage by 200 mV.

enumerator kSLCD_VolatgeTrimIncrease250mV
Increase the voltage by 250 mV.

enumerator kSLCD_VolatgeTrimIncrease300mV
Increase the voltage by 300 mV.

enumerator kSLCD_VolatgeTrimIncrease350mV
Increase the voltage by 350 mV.

enumerator kSLCD_VolatgeTrimDecrease400mV
Decrease the voltage by 400 mV.

enumerator kSLCD_VolatgeTrimDecrease350mV
Decrease the voltage by 350 mV.

enumerator kSLCD_VolatgeTrimDecrease300mV
Decrease the voltage by 300 mV.

enumerator kSLCD_VolatgeTrimDecrease250mV
Decrease the voltage by 250 mV.

enumerator kSLCD_VolatgeTrimDecrease200mV
Decrease the voltage by 200 mV.

enumerator kSLCD_VolatgeTrimDecrease150mV
Decrease the voltage by 150 mV.

enumerator kSLCD_VolatgeTrimDecrease100mV
Decrease the voltage by 100 mV.

enumerator kSLCD_VolatgeTrimDecrease50mV
Decrease the voltage by 50 mV.

enum _slcd_sample_hold
SLCD sample&hold configuration. To save power, configure the voltage to be sampled and held periodically, during this period the phase switches are turned off.

Values:

enumerator kSLCD_SampleHoldNone
No sample&hold.

enumerator kSLCD_SampleHold64Cycle
Sample&hold each 64 function clock cycle.

enumerator kSLCD_SampleHold128Cycle
Sample&hold each 128 function clock cycle.

enum _slcd_blink_rate
SLCD blink rate.

Values:

enumerator kSLCD_BlinkRate00
SLCD blink rate is LCD clock/((2^11)).

enumerator kSLCD_BlinkRate01
SLCD blink rate is LCD clock/((2^12)).

enumerator kSLCD_BlinkRate02
SLCD blink rate is LCD clock/((2^13)).

enumerator kSLCD_BlinkRate03
SLCD blink rate is LCD clock/((2^14)).

enumerator kSLCD_BlinkRate04
SLCD blink rate is LCD clock/((2^15)).

enumerator kSLCD_BlinkRate05
SLCD blink rate is LCD clock/((2^16)).

enumerator kSLCD_BlinkRate06
SLCD blink rate is LCD clock/((2^17)).

enumerator kSLCD_BlinkRate07
SLCD blink rate is LCD clock/((2^18)).

enum _slcd_duty_cycle

SLCD duty cycle.

Values:

enumerator kSLCD_1Div1DutyCycle

LCD use 1 BP 1/1 duty cycle.

enumerator kSLCD_1Div2DutyCycle

LCD use 2 BP 1/2 duty cycle.

enumerator kSLCD_1Div3DutyCycle

LCD use 3 BP 1/3 duty cycle.

enumerator kSLCD_1Div4DutyCycle

LCD use 4 BP 1/4 duty cycle.

enum _slcd_phase_type

SLCD segment phase type.

Values:

enumerator kSLCD_NoPhaseActivate

LCD wareform no phase activates.

enumerator kSLCD_PhaseAActivate

LCD waveform phase A activates.

enumerator kSLCD_PhaseBActivate

LCD waveform phase B activates.

enumerator kSLCD_PhaseCActivate

LCD waveform phase C activates.

enumerator kSLCD_PhaseDActivate

LCD waveform phase D activates.

enum _slcd_phase_index

SLCD segment phase bit index.

Values:

enumerator kSLCD_PhaseAIndex

LCD phase A bit index.

enumerator kSLCD_PhaseBIndex

LCD phase B bit index.

enumerator kSLCD_PhaseCIndex

LCD phase C bit index.

enumerator kSLCD_PhaseDIndex
LCD phase D bit index.

enum _slcd_display_mode
SLCD display mode.
Values:

enumerator kSLCD_NormalMode
LCD Normal display mode.

enumerator kSLCD_AlternateMode
LCD Alternate display mode. For four back planes or less.

enumerator kSLCD_BlankMode
LCD Blank display mode.

enum _slcd_blink_mode
SLCD blink mode.
Values:

enumerator kSLCD_BlankDisplayBlink
Display blank during the blink period.

enumerator kSLCD_AltDisplayBlink
Display alternate display during the blink period if duty cycle is lower than 5.

enum _slcd_fault_detect_clock_prescaler
SLCD fault detect clock prescaler.
Values:

enumerator kSLCD_FaultSampleFreqDivider1
Fault detect sample clock frequency is 1/1 bus clock.

enumerator kSLCD_FaultSampleFreqDivider2
Fault detect sample clock frequency is 1/2 bus clock.

enumerator kSLCD_FaultSampleFreqDivider4
Fault detect sample clock frequency is 1/4 bus clock.

enumerator kSLCD_FaultSampleFreqDivider8
Fault detect sample clock frequency is 1/8 bus clock.

enumerator kSLCD_FaultSampleFreqDivider16
Fault detect sample clock frequency is 1/16 bus clock.

enumerator kSLCD_FaultSampleFreqDivider32
Fault detect sample clock frequency is 1/32 bus clock.

enumerator kSLCD_FaultSampleFreqDivider64
Fault detect sample clock frequency is 1/64 bus clock.

enumerator kSLCD_FaultSampleFreqDivider128
Fault detect sample clock frequency is 1/128 bus clock.

enum _slcd_fault_detect_sample_window_width
SLCD fault detect sample window width.
Values:

enumerator kSLCD_FaultDetectWindowWidth4SampleClk
Sample window width is 4 sample clock cycles.

enumerator kSLCD_FaultDetectWindowWidth8SampleClk
Sample window width is 8 sample clock cycles.

enumerator kSLCD_FaultDetectWindowWidth16SampleClk
Sample window width is 16 sample clock cycles.

enumerator kSLCD_FaultDetectWindowWidth32SampleClk
Sample window width is 32 sample clock cycles.

enumerator kSLCD_FaultDetectWindowWidth64SampleClk
Sample window width is 64 sample clock cycles.

enumerator kSLCD_FaultDetectWindowWidth128SampleClk
Sample window width is 128 sample clock cycles.

enumerator kSLCD_FaultDetectWindowWidth256SampleClk
Sample window width is 256 sample clock cycles.

enumerator kSLCD_FaultDetectWindowWidth512SampleClk
Sample window width is 512 sample clock cycles.

enum _slcd_interrupt_enable
SLCD interrupt source.
Values:

enumerator kSLCD_FaultDetectCompleteInterrupt
SLCD fault detection complete interrupt source.

enumerator kSLCD_FrameFreqInterrupt
SLCD frame frequency interrupt source. Not available in all low-power modes.

enum _slcd_lowpower_behavior
SLCD behavior in low power mode.
Values:

enumerator kSLCD_EnabledInWaitStop
SLCD works in wait and stop mode.

enumerator kSLCD_EnabledInWaitOnly
SLCD works in wait mode and is disabled in stop mode.

enumerator kSLCD_EnabledInStopOnly
SLCD works in stop mode and is disabled in wait mode.

enumerator kSLCD_DisabledInWaitStop
SLCD is disabled in stop mode and wait mode.

typedef enum *_slcd_clock_prescaler* slcd_clock_prescaler_t
SLCD clock prescaler to generate frame frequency.

typedef enum *_slcd_regulated_voltage_trim* slcd_regulated_voltage_trim_t
SLCD regulated voltage trim parameter, be used to meet the desired contrast.

typedef enum *_slcd_sample_hold* slcd_sample_hold_t
SLCD sample&hold configuration. To save power, configure the voltage to be sampled and held periodically, during this period the phase switches are turned off.

typedef enum *_slcd_blink_rate* slcd_blink_rate_t
SLCD blink rate.

typedef enum *_slcd_duty_cycle* slcd_duty_cycle_t
SLCD duty cycle.

typedef enum *_slcd_phase_type* slcd_phase_type_t
SLCD segment phase type.

typedef enum *_slcd_phase_index* slcd_phase_index_t
SLCD segment phase bit index.

typedef enum *_slcd_display_mode* slcd_display_mode_t
SLCD display mode.

typedef enum *_slcd_blink_mode* slcd_blink_mode_t
SLCD blink mode.

typedef enum *_slcd_fault_detect_clock_prescaler* slcd_fault_detect_clock_prescaler_t
SLCD fault detect clock prescaler.

typedef enum *_slcd_fault_detect_sample_window_width*
slcd_fault_detect_sample_window_width_t
SLCD fault detect sample window width.

typedef enum *_slcd_interrupt_enable* slcd_interrupt_enable_t
SLCD interrupt source.

typedef enum *_slcd_lowpower_behavior* slcd_lowpower_behavior

SLCD behavior in low power mode.

typedef struct *_slcd_fault_detect_config* slcd_fault_detect_config_t

SLCD fault frame detection configuration structure.

typedef struct *_slcd_config* slcd_config_t

SLCD configuration structure.

struct _slcd_fault_detect_config

#include <fsl_slcd.h> SLCD fault frame detection configuration structure.

Public Members

bool faultDetectIntEnable

Fault frame detection interrupt enable flag.

bool faultDetectBackPlaneEnable

True means the pin id fault detected is back plane otherwise front plane.

uint8_t faultDetectPinIndex

Fault detected pin id from 0 to (LCD_WFOVERLAY_WFACCESS32BIT_WF_COUNT * 4 - 1).

slcd_fault_detect_clock_prescaler_t faultPrescaler

Fault detect clock prescaler.

slcd_fault_detect_sample_window_width_t width

Fault detect sample window width.

struct _slcd_config

#include <fsl_slcd.h> SLCD configuration structure.

Public Members

bool lowPowerWaveform

Generate low power waveform.

slcd_regulated_voltage_trim_t voltageTrimVLL1

Voltage trim for VLL1 output level.

slcd_regulated_voltage_trim_t voltageTrimVLL2

Voltage trim for VLL2 output level.

slcd_sample_hold_t sampleHold

Sample&hold setting.

slcd_display_mode_t displayMode

SLCD display mode.

slcd_duty_cycle_t dutyCycle

Duty cycle.

slcd_lowpower_behavior lowPowerBehavior

SLCD behavior in low power mode.

bool frameFreqIntEnable

Frame frequency interrupt enable flag.

uint32_t slcdLowPinEnabled

Setting enabled SLCD pin 0 ~ pin 31. Setting bit n to 1 means enable pin n.

uint32_t slcdHighPinEnabled

Setting enabled SLCD pin 32 ~ pin (LCD_WFOVERLAY_WFACCESS32BIT_WF_COUNT * 4 - 1). Setting bit n to 1 means enable pin (n + 32).

uint32_t backPlaneLowPin

Setting back plane pin 0 ~ pin 31. Setting bit n to 1 means setting pin n as back plane. It should never have the same bit setting as the frontPlane Pin.

uint32_t backPlaneHighPin

Setting back plane pin 32 ~ pin (LCD_WFOVERLAY_WFACCESS32BIT_WF_COUNT * 4 - 1). Setting bit n to 1 means setting pin (n + 32) as back plane. It should never have the same bit setting as the frontPlane Pin.

slcd_fault_detect_config_t *faultConfig

Fault frame detection configure. If not requirement, set to NULL.

2.70 SMARTDMA: SMART DMA Driver

typedef void (*smartdma_callback_t)(void *param)

Callback function prototype for the smartdma driver.

void SMARTDMA_Init(uint32_t apiMemAddr, const void *firmware, uint32_t firmwareSizeByte)

Initialize the SMARTDMA.

Deprecated:

Do not use this function. It has been superceded by *SMARTDMA_InitWithoutFirmware* and *SMARTDMA_InstallFirmware*.

Parameters

- apiMemAddr – The address firmware will be copied to.
- firmware – The firmware to use.

- firmwareSizeByte – Size of firmware.

void SMARTDMA_InitWithoutFirmware(void)

Initialize the SMARTDMA.

This function is similar with *SMARTDMA_Init*, the difference is this function does not install the firmware, the firmware could be installed using *SMARTDMA_InstallFirmware*.

void SMARTDMA_InstallFirmware(uint32_t apiMemAddr, const void *firmware, uint32_t firmwareSizeByte)

Install the firmware.

Note: Only call this function when SMARTDMA is not busy.

Parameters

- apiMemAddr – The address firmware will be copied to.
- firmware – The firmware to use.
- firmwareSizeByte – Size of firmware.

void SMARTDMA_InstallCallback(*smartdma_callback_t* callback, void *param)

Install the complete callback function.

Note: Only call this function when SMARTDMA is not busy.

Parameters

- callback – The callback called when smartdma program finished.
- param – Parameter for the callback.

void SMARTDMA_Boot(uint32_t apiIndex, void *pParam, uint8_t mask)

Boot the SMARTDMA to run program.

Note: Only call this function when SMARTDMA is not busy.

Note: The memory *pParam shall not be freed before the SMARTDMA function finished.

Parameters

- apiIndex – Index of the API to call.
- pParam – Pointer to the parameter allocated by caller.
- mask – Value set to register SMARTDMA->ARM2EZH[0:1].

void SMARTDMA_Boot1(uint32_t apiIndex, const *smartdma_param_t* *pParam, uint8_t mask)

Copy SMARTDMA params and Boot to run program.

This function is similar with *SMARTDMA_Boot*, the only difference is, this function copies the *pParam to a local variable, upper layer can free the pParam's memory before the SMARTDMA execution finished, for example, upper layer can define the param as a local variable.

Note: Only call this function when SMARTDMA is not busy.

Parameters

- apiIndex – Index of the API to call.
- pParam – Pointer to the parameter.
- mask – Value set to SMARTDMA_ARM2SMARTDMA[0:1].

void SMARTDMA_Deinit(void)
Deinitialize the SMARTDMA.

void SMARTDMA_Reset(void)
Reset the SMARTDMA.

void SMARTDMA_HandleIRQ(void)
SMARTDMA IRQ.

void SMARTDMA_SetExternalFlag(uint8_t flag)
SMARTDMA set EX flag.

void SMARTDMA_AccessShareRAM(uint8_t flag)
SMARTDMA access RAM.

FSL_SMARTDMA_DRIVER_VERSION
SMARTDMA driver version.

2.71 MCXN SMARTDMA Firmware

enum _smartdma_display_api
The API index when using s_smartdmaDisplayFirmware.
Values:

enumerator kSMARTDMA_FlexIO_DMA

enum _smartdma_camera_api
The API index when using s_smartdmaCameraFirmware.
Values:

enumerator kSMARTDMA_FlexIO_CameraWholeFrame

enumerator kSMARTDMA_FlexIO_CameraDiv16Frame
Deprecated. Use kSMARTDMA_CameraWholeFrameQVGA instead.

enumerator kSMARTDMA_CameraWholeFrameQVGA
Deprecated. Use kSMARTDMA_CameraDiv16FrameQVGA instead.
Save whole frame of QVGA(320x240) to buffer in each interrupt in RGB565 format.

enumerator kSMARTDMA_CameraDiv16FrameQVGA

Save 1/16 frame of QVGA(320x240) to buffer in each interrupt in RGB565 format, takes 16 interrupts to get the whole frame.

enumerator kSMARTDMA_CameraWholeFrame480_320

Save whole frame of 480x320 to buffer in each interrupt in RGB565 format.

enumerator kSMARTDMA_CameraDiv4FrameQVGAGrayScale

Save 1/4 frame of QVGA(320x240) to buffer in each interrupt in grayscale format, takes 4 interrupts to get the whole frame.

enumerator kSMARTDMA_CameraDiv16FrameQVGAGrayScale

Save 1/16 frame of QVGA(320x240) to buffer in each interrupt in grayscale format, takes 16 interrupts to get the whole frame.

enumerator kSMARTDMA_CameraDiv16Frame384_384

Save 1/16 frame of 384x384 to buffer in each interrupt in grayscale format, takes 16 interrupts to get the whole frame.

enumerator kSMARTDMA_CameraWholeFrame320_480

Save whole frame of 320x480 to buffer in each interrupt in RGB565 format.

enum _smartdma_keyscan_api

The API index when using s_smartdmaKeyscanFirmware.

Values:

enumerator kSMARTDMA_Keyscan_4x4

Using SmartDma to control GPIO.

typedef struct *_smartdma_flexio_mculcd_param* smartdma_flexio_mculcd_param_t

Parameter for FlexIO MCULCD.

typedef struct *_smartdma_camera_param* smartdma_camera_param_t

Parameter for camera.

typedef struct *_smartdma_keyscan_4x4_param* smartdma_keyscan_4x4_param_t

Parameter for keyscan 4x4.

const uint8_t s_smartdmaDisplayFirmware[]

The firmware used for display.

const uint32_t s_smartdmaDisplayFirmwareSize

Size of s_smartdmaDisplayFirmware.

const uint8_t s_smartdmaCameraFirmware[]

The firmware used for camera.

const uint32_t s_smartdmaCameraFirmwareSize

Size of s_smartdmacameraFirmware.

const uint8_t s_smartdmaKeyscanFirmware[]
: The firmware used for keyscan.

const uint32_t s_smartdmaKeyscanFirmwareSize
: Size of s_smartdmaKeyscanFirmware.

FSL_SMARTDMA_MCXA_DRIVER_VERSION
: SMARTDMA driver version.

SMARTDMA_DISPLAY_MEM_ADDR
: The s_smartdmaDisplayFirmware firmware memory address.

SMARTDMA_DISPLAY_FIRMWARE_SIZE
: Size of s_smartdmaDisplayFirmware.

SMARTDMA_CAMERA_MEM_ADDR
: The s_smartdmaCameraFirmware firmware memory address.

SMARTDMA_CAMERA_FIRMWARE_SIZE
: Size of s_smartdmacameraFirmware.

SMARTDMA_KEYSCAN_MEM_ADDR
: The s_smartdmaKeyscanFirmware firmware memory address.

SMARTDMA_KEYSCAN_FIRMWARE_SIZE
: Size of s_smartdmaKeyscanFirmware.

uint32_t *p_buffer

uint32_t buffersize

uint32_t *smartdma_stack

uint32_t *smartdma_stack
: Stack used by SMARTDMA, shall be at least 64 bytes.

uint32_t *p_buffer
: Buffer to store the received camera data.

uint32_t *p_stripe_index
: Pointer to stripe index. Used when only partial frame is received per interrupt.

uint32_t *p_buffer_ping_pong
: Buffer to store the 2nd stripe of camera data. Used when only partial frame is received per interrupt.

smartdma_flexio_mculcd_param_t flexioMcuLcdParam
: Parameter for flexio MCULCD.

smartdma_camera_param_t cameraParam
Parameter for camera.

uint32_t *smartdma_stack
Stack used by SMARTDMA, shall be at least 64 bytes.

uint32_t *p_gpio_reg
Buffer to provide GPIO register for COL1, COL2, COL3, COL4, ROW1, ROW2, ROW3, ROW4.

uint32_t *p_keyvalue
Buffer to store key value.

uint32_t *p_keycan_interval
Delay how many system clock cycles.

struct _smartdma_flexio_mculcd_param
#include <fsl_smartdma_fw.h> Parameter for FlexIO MCULCD.

struct _smartdma_camera_param
#include <fsl_smartdma_fw.h> Parameter for camera.

union smartdma_param_t
#include <fsl_smartdma_fw.h> Parameter for all supported APIs.

struct _smartdma_keyscan_4x4_param
#include <fsl_smartdma_fw.h> Parameter for keyscan 4x4.

2.72 Digital Tamper

2.73 TDET

status_t TDET_Init(DIGTMP_Type *base)
Initialize TDET.

This function initializes TDET.

Parameters

- base – TDET peripheral base address

Returns
Status of the init operation

void TDET_Deinit(DIGTMP_Type *base)
Deinitialize TDET.

This function disables glitch filters and active tampers This function disables the TDET clock and prescaler in TDET Control Register.

Parameters

- base – TDET peripheral base address

void TDET_GetDefaultConfig(DIGTMP_Type *base, *tdet_config_t* *defaultConfig)

Gets default values for the TDET Control Register.

This function fills the given structure with default values for the TDET Control Register. The default values are:

```
defaultConfig->innerClockAndPrescalerEnable = true
defaultConfig->tamperForceSystemResetEnable = false
defaultConfig->updateMode = kTDET_StatusLockWithTamper
defaultConfig->clockSourceActiveTamper0 = kTDET_ClockType1Hz
defaultConfig->clockSourceActiveTamper1 = kTDET_ClockType1Hz
defaultConfig->prescaler = 0
```

Parameters

- base – TDET peripheral base address
- defaultConfig – **[out]** Pointer to structure to be filled with default parameters

status_t TDET_SetConfig(DIGTMP_Type *base, const *tdet_config_t* *config)

Writes to the TDET Control Register.

This function writes the given structure to the TDET Control Register.

Parameters

- base – TDET peripheral base address
- config – Pointer to structure with TDET peripheral configuration parameters

Returns

kStatus_Fail when writing to TDET Control Register is not allowed

Returns

kStatus_Success when operation completes successfully

status_t TDET_SoftwareReset(DIGTMP_Type *base)

Software reset.

This function resets all TDET registers. The CR[SWR] itself is not affected; it is reset by VBAT POR only.

Parameters

- base – TDET peripheral base address

Returns

kStatus_Fail when writing to TDET Control Register is not allowed

Returns

kStatus_Success when operation completes successfully

void TDET_PinGetDefaultConfig(DIGTMP_Type *base, *tdet_pin_config_t* *pinConfig)

Gets default values for tamper pin configuration.

This function fills the give structure with default values for the tamper pin and glitch filter configuration. The default values are: code pinConfig->pinPolarity = kTDET_TamperPinPolarityExpectNormal; pinConfig->pinDirection = kTDET_TamperPinDirectionIn; pinConfig->tamperPullEnable = false; pinConfig->tamperPinSampleFrequency = kTDET_GlitchFilterSamplingEveryCycle8; pinConfig->tamperPinSampleWidth = kTDET_GlitchFilterSampleDisable;

pinConfig->glitchFilterEnable = false; pinConfig->glitchFilterPrescaler = kTDET_GlitchFilterClock512Hz; pinConfig->glitchFilterWidth = 0; pinConfig->tamperPinExpected = kTDET_GlitchFilterExpectedLogicZero; pinConfig->tamperPullSelect = kTDET_GlitchFilterPullTypeAssert; endcode

Parameters

- base – TDET peripheral base address
- pinConfig – **[out]** Pointer to structure to be filled with tamper pins default parameters

status_t TDET_PinSetConfig(DIGTMP_Type *base, const *tdet_pin_config_t* *pinConfig, uint32_t pinSelect)

Writes the tamper pin configuration.

This function writes per pin parameters to tamper pin and glitch filter configuration registers.

Parameters

- base – TDET peripheral base address
- pinConfig – Pointer to structure with tamper pin and glitch filter configuration parameters
- pinSelect – Bit mask for tamper pins to be configured. The passed value is combination of enum _tdet_tamper_pin (tdet_tamper_pin_t) values (OR'ed).

Returns

kStatus_Fail when writing to TDET Pin Direction, Pin Polarity or Glitch Filter Register(s) is not allowed

Returns

kStatus_Success when operation completes successfully

status_t TDET_GetStatusFlags(DIGTMP_Type *base, uint32_t *result)

Reads the Status Register.

This function reads flag bits from TDET Status Register.

Parameters

- base – TDET peripheral base address
- result – **[out]** Pointer to uint32_t where to write Status Register read value. Use tdet_status_flag_t to decode individual flags.

Returns

kStatus_Fail when Status Register reading is not allowed

Returns

kStatus_Success when result is written with the Status Register read value

status_t TDET_ClearStatusFlags(DIGTMP_Type *base, uint32_t mask)

Writes to the Status Register.

This function clears specified flag bits in TDET Status Register.

Parameters

- base – TDET peripheral base address
- mask – Bit mask for the flag bits to be cleared. Use tdet_status_flag_t to encode flags.

Returns

kStatus_Fail when Status Register writing is not allowed

Returns
kStatus_Success when mask is written to the Status Register

status_t TDET_EnableInterrupts(DIGTMP_Type *base, uint32_t mask)

Writes to the Interrupt Enable Register.

This function sets specified interrupt enable bits in TDET Interrupt Enable Register.

Parameters

- base – TDET peripheral base address
- mask – Bit mask for the interrupt enable bits to be set.

Returns
kStatus_Fail when Interrupt Enable Register writing is not allowed

Returns
kStatus_Success when mask is written to the Interrupt Enable Register

status_t TDET_DisableInterrupts(DIGTMP_Type *base, uint32_t mask)

Writes to the Interrupt Enable Register.

This function clears specified interrupt enable bits in TDET Interrupt Enable Register.

Parameters

- base – TDET peripheral base address
- mask – Bit mask for the interrupt enable bits to be cleared.

Returns
kStatus_Fail when Interrupt Enable Register writing is not allowed

Returns
kStatus_Success when specified bits are cleared in the Interrupt Enable Register

status_t TDET_EnableTampers(DIGTMP_Type *base, uint32_t mask)

Writes to the Tamper Enable Register.

This function sets specified tamper enable bits in TDET Tamper Enable Register.

Parameters

- base – TDET peripheral base address
- mask – Bit mask for the tamper enable bits to be set.

Returns
kStatus_Fail when Tamper Enable Register writing is not allowed

Returns
kStatus_Success when mask is written to the Tamper Enable Register

status_t TDET_DisableTampers(DIGTMP_Type *base, uint32_t mask)

Writes to the Tamper Enable Register.

This function clears specified tamper enable bits in TDET Tamper Enable Register.

Parameters

- base – TDET peripheral base address
- mask – Bit mask for the tamper enable bits to be cleared.

Returns
kStatus_Fail when Tamper Enable Register writing is not allowed

Returns
kStatus_Success when specified bits are cleared in the Tamper Enable Register

status_t TDET_ForceTamper(DIGTMP_Type *base)

Writes to the Tamper Seconds Register.

This function writes to TDET Tamper Seconds Register. This causes Status Register DTF flag to be set (TDET tampering detected).

Parameters

- base – TDET peripheral base address

Returns

kStatus_Fail when Tamper Seconds Register writing is not allowed

Returns

kStatus_Success when Tamper Seconds Register is written

status_t TDET_GetTamperTimeSeconds(DIGTMP_Type *base, uint32_t *tamperTimeSeconds)

Reads the Tamper Seconds Register.

This function reads TDET Tamper Seconds Register. The read value returns the time in seconds at which the Status Register DTF flag was set.

Parameters

- base – TDET peripheral base address
- tamperTimeSeconds – Time in seconds at which the tamper detection SR[DTF] flag was set.

Returns

kStatus_Fail when Tamper Seconds Register reading is not allowed

Returns

kStatus_Success when Tamper Seconds Register is read

void TDET_LockRegisters(DIGTMP_Type *base, uint32_t mask)

Writes to the TDET Lock Register.

This function clears specified lock bits in the TDET Lock Register. When a lock bit is clear, a write to corresponding TDET Register is ignored. Once cleared, these bits can only be set by VBAT POR or software reset.

Parameters

- base – TDET peripheral base address
- mask – Bit mask for the lock bits to be cleared. Use tdet_register_t values to encode (OR'ed) which TDET Registers shall be locked.

FSL_TDET_DRIVER_VERSION

Defines TDET driver version 2.4.0.

Change log:

- Version 2.4.0
  - Added support for MIMXRT2663.
- Version 2.3.3
  - Fix MISRA and CERT-C findings.
- Version 2.3.2
  - Added common IRQ handler entry TDET_DriverIRQHandler.
- Version 2.3.1
  - Added support for KW43 device.

- Version 2.3.0
  - Added enum for TIF10.
- Version 2.2.0
  - Added support for chips without active tamper pins.
- Version 2.1.1
  - Added clearing SR_TAF and SR_DTF into *TDET_Init()*.
  - Fix typo in kTDET_ClockType64Hz comment
- Version 2.1.0
  - Added setting of disabling prescaler on tamper event into *TDET_SetConfig()* and TDET_GetDefaultConfig functions.
- Version 2.0.0
  - Initial version

enum _tdet_update_mode

TDET Update Mode.

These constants allow TDET interrupts to be cleared if no tampering has been detected, while still preventing the TDET Tamper Flag (SR[DTF]) from being cleared once it is set.

Values:

enumerator kTDET_StatusLockNormal

TDET Status Register cannot be written when the Status Register Lock bit within the Lock Register (LR[SRL]) is clear

enumerator kTDET_StatusLockWithTamper

TDET Status Register cannot be written when the Status Register Lock bit within the Lock Register (LR[SRL]) is clear and TDET Tamper Flag (SR[DTF]) is set

enum _tdet_active_tamper_clock

TDET Active Tamper Clock Source.

These constants define the clock source for Active Tamper Shift Register to configure in a TDET base.

Values:

enumerator kTDET_ClockType1Hz

clocked by 1 Hz prescaler clock

enumerator kTDET_ClockType64Hz

clocked by 64 Hz prescaler clock

enum _tdet_pin_polarity

TDET Tamper Pin Polarity.

These constants define tamper pin polarity to configure in a TDET base.

Values:

enumerator kTDET_TamperPinPolarityExpectNormal

Tamper pin expected value is not inverted

enumerator kTDET_TamperPinPolarityExpectInverted
Tamper pin expected value is inverted

enum _tdet_pin_direction
TDET Tamper Pin Direction.

These constants define tamper pin direction to configure in a TDET base.

Values:

enumerator kTDET_TamperPinDirectionIn
Tamper pins configured as input

enumerator kTDET_TamperPinDirectionOut
Tamper pins configured as output, drives inverse of expected value

enum _tdet_glitch_filter_sample_freq
TDET Glitch Filter Tamper Pin Sample Frequency.

These constants define tamper pin glitch filter sample frequency to configure in a TDET base.

Values:

enumerator kTDET_GlitchFilterSamplingEveryCycle8
Sample once every 8 cycles

enumerator kTDET_GlitchFilterSamplingEveryCycle32
Sample once every 32 cycles

enumerator kTDET_GlitchFilterSamplingEveryCycle128
Sample once every 128 cycles

enumerator kTDET_GlitchFilterSamplingEveryCycle512
Sample once every 512 cycles

enum _tdet_glitch_filter_sample_width
TDET Glitch Filter Tamper Pin Sample Width.

These constants define tamper pin glitch filter sample width to configure in a TDET base.

Values:

enumerator kTDET_GlitchFilterSampleDisable
Sampling disabled

enumerator kTDET_GlitchFilterSampleCycle2
Sample width pull enable/input buffer enable=2 cycles/1 cycle

enumerator kTDET_GlitchFilterSampleCycle4
Sample width pull enable/input buffer enable=4 cycles/2 cycles

enumerator kTDET_GlitchFilterSampleCycle8
Sample width pull enable/input buffer enable=8 cycles/4 cycles

enum _tdet_glitch_filter_prescaler
TDET Glitch Filter Tamper Pin Clock Source.
These constants define tamper pin glitch filter clock source to configure in a TDET base.
Values:

enumerator kTDET_GlitchFilterClock512Hz
Glitch Filter on tamper pin is clocked by the 512 Hz prescaler clock

enumerator kTDET_GlitchFilterClock32768Hz
Glitch Filter on tamper pin is clocked by the 32768 Hz prescaler clock

enum _tdet_glitch_filter_expected
TDET Glitch Filter Tamper Pin Expected Value.
These constants define tamper pin glitch filter expected value to configure in a TDET base.
Values:

enumerator kTDET_GlitchFilterExpectedLogicZero
Expected value is logic zero

enumerator kTDET_GlitchFilterExpectedActTamperOut0
Expected value is active tamper 0 output

enumerator kTDET_GlitchFilterExpectedActTamperOut1
Expected value is active tamper 1 output

enumerator kTDET_GlitchFilterExpectedActTamperOutXOR
Expected value is active tamper 0 output XORed with active tamper 1 output

enum _tdet_glitch_filter_pull
TDET Glitch Filter Tamper Pull Select.
These constants define tamper pin glitch filter pull direction to configure in a TDET base.
Values:

enumerator kTDET_GlitchFilterPullTypeAssert
Tamper pin pull direction always asserts the tamper pin.

enumerator kTDET_GlitchFilterPullTypeNegate
Tamper pin pull direction always negates the tamper pin.

enum _tdet_external_tamper_pin
List of TDET external tampers.
Values:

enumerator kTDET_ExternalTamper0

enumerator kTDET_ExternalTamper1

enumerator kTDET_ExternalTamper2

enumerator kTDET_ExternalTamper3

enumerator kTDET_ExternalTamper4

enumerator kTDET_ExternalTamper5

enumerator kTDET_ExternalTamper6

enumerator kTDET_ExternalTamper7

enum _tdet_active_tamper_register

TDET Active Tamper Register Select.

These constants are used to define activeTamperRegisterSelect argument to be used with TDET_ActiveTamperConfigure().

Values:

enumerator kTDET_ActiveTamperRegister0

enumerator kTDET_ActiveTamperRegister1

enum _tdet_status_flag

TDET Status Register flags.

This provides constants for the TDET Status Register.

Values:

enumerator kTDET_StatusTamperFlag

TDET Digital Tamper Flag

enumerator kTDET_StatusTamperAcknowledgeFlag

TDET Tamper Acknowledge Flag

enumerator kTDET_TIF0

TDET Tamper input 0

enumerator kTDET_StatusTamperPinTamper0

TDET Tamper Pin 0 Tamper detected

enumerator kTDET_StatusTamperPinTamper1

TDET Tamper Pin 1 Tamper detected

enumerator kTDET_StatusAll
Mask for all of the TDET Status Register bits

enum _tdet_interrupt
TDET Interrupt Enable Register.
This provides constants for the TDET Interrupt Enable Register.
Values:

enumerator kTDET_InterruptTamper
TDET Digital Tamper Interrupt

enumerator kTDET_InterruptTIF0
TDET TIF0 Interrupt

enumerator kTDET_InterruptTamperPinTamper0
TDET Tamper Pin Tamper 0 Interrupt

enumerator kTDET_InterruptTamperPinTamper1
TDET Tamper Pin Tamper 1 Interrupt

enumerator kTDET_InterruptTamperPinTamper_All
TDET All Tamper Pins Interrupt

enumerator kTDET_InterruptAll
Mask to select all TDET Interrupt Enable Register bits

enum _tdet_tamper
TDET Tamper Enable Register.
This provides constants for the TDET Tamper Enable Register.
Values:

enumerator kTDET_TamperTIF0
TIF0 Tamper Enable

enumerator kTDET_TamperTamperPin0
Tamper Pin 0 Tamper Enable

enumerator kTDET_TamperTamperPin1
Tamper Pin 1 Tamper Enable

enumerator kTDET_TamperTamperPinAll
All Tamper Pin Tamper Enable

enumerator kTDET_TamperAll
Mask to select all Tamper Enable Register bits

enum __tdet__register

TDET Registers.

This provides constants to encode a mask for the TDET Registers.

Values:

enumerator kTDET__NoRegister

No Register

enumerator kTDET__Control

Control Register

enumerator kTDET__Status

Status Register

enumerator kTDET__Lock

Lock Register

enumerator kTDET__InterruptEnable

Interrupt Enable Register

enumerator kTDET__TamperSeconds

Tamper Seconds Register

enumerator kTDET__TamperEnable

Tamper Enable Register

enumerator kTDET__PinPolarity

Pin Polarity Register

enumerator kTDET__GlitchFilter0

Glitch Filter Register 0

enumerator kTDET__GlitchFilter1

Glitch Filter Register 1

enumerator kTDET__PinConfigurationRegisters

Mask to select all TDET Pin Configuration Registers

enumerator kTDET__AllRegisters

Mask to select all TDET Registers

typedef enum *_tdet_update_mode* tdet__update__mode__t

TDET Update Mode.

These constants allow TDET interrupts to be cleared if no tampering has been detected, while still preventing the TDET Tamper Flag (SR[DTF]) from being cleared once it is set.

typedef enum *_tdet_active_tamper_clock* tdet_active_tamper_clock_t

TDET Active Tamper Clock Source.

These constants define the clock source for Active Tamper Shift Register to configure in a TDET base.

typedef struct *_tdet_config* tdet_config_t

TDET Control Register.

This structure defines values for TDET Control Register.

typedef enum *_tdet_pin_polarity* tdet_pin_polarity_t

TDET Tamper Pin Polarity.

These constants define tamper pin polarity to configure in a TDET base.

typedef enum *_tdet_pin_direction* tdet_pin_direction_t

TDET Tamper Pin Direction.

These constants define tamper pin direction to configure in a TDET base.

typedef enum *_tdet_glitch_filter_sample_freq* tdet_glitch_filter_sample_freq_t

TDET Glitch Filter Tamper Pin Sample Frequency.

These constants define tamper pin glitch filter sample frequency to configure in a TDET base.

typedef enum *_tdet_glitch_filter_sample_width* tdet_glitch_filter_sample_width_t

TDET Glitch Filter Tamper Pin Sample Width.

These constants define tamper pin glitch filter sample width to configure in a TDET base.

typedef enum *_tdet_glitch_filter_prescaler* tdet_glitch_filter_prescaler_t

TDET Glitch Filter Tamper Pin Clock Source.

These constants define tamper pin glitch filter clock source to configure in a TDET base.

typedef enum *_tdet_glitch_filter_expected* tdet_glitch_filter_expected_t

TDET Glitch Filter Tamper Pin Expected Value.

These constants define tamper pin glitch filter expected value to configure in a TDET base.

typedef enum *_tdet_glitch_filter_pull* tdet_glitch_filter_pull_t

TDET Glitch Filter Tamper Pull Select.

These constants define tamper pin glitch filter pull direction to configure in a TDET base.

typedef struct *_tdet_pin_config* tdet_pin_config_t

TDET Tamper Pin configuration registers.

This structure defines values for TDET Pin Direction, Pin Polarity, and Glitch Filter registers.

typedef enum *_tdet_external_tamper_pin* tdet_external_tamper_pin_t

List of TDET external tampers.

typedef enum *_tdet_active_tamper_register* tdet_active_tamper_register_t

TDET Active Tamper Register Select.

These constants are used to define activeTamperRegisterSelect argument to be used with TDET_ActiveTamperConfigure().

typedef struct *_tdet_active_tamper_config* tdet_active_tamper_config_t

TDET Active Tamper registers.

This structure defines values for TDET Active Tamper Registers.

typedef enum *_tdet_status_flag* tdet_status_flag_t

TDET Status Register flags.

This provides constants for the TDET Status Register.

typedef enum *_tdet_interrupt* tdet_interrupt_t

TDET Interrupt Enable Register.

This provides constants for the TDET Interrupt Enable Register.

typedef enum *_tdet_tamper* tdet_tamper_t

TDET Tamper Enable Register.

This provides constants for the TDET Tamper Enable Register.

typedef enum *_tdet_register* tdet_register_t

TDET Registers.

This provides constants to encode a mask for the TDET Registers.

void VBAT0_DriverIRQHandler(void)

struct __tdet_config

#include <fsl_tdet.h> TDET Control Register.

This structure defines values for TDET Control Register.

Public Members

bool innerClockAndPrescalerEnable

Enable/disable 32768 Hz clock within TDET and the TDET prescaler that generates 512 Hz, 64Hz and 1 Hz prescaler clocks

bool tamperForceSystemResetEnable

Enable/disable assertion of chip reset when tampering is detected

enum *_tdet_update_mode* updateMode

Selects update mode for TDET Status Register

enum *_tdet_active_tamper_clock* clockSourceActiveTamper0

Selects clock source for Active Tamper Shift Register 0

enum *_tdet_active_tamper_clock* clockSourceActiveTamper1

Selects clock source for Active Tamper Shift Register 1

bool disablePrescalerAfterTamper

Allows the 32-KHz clock and prescaler to be automatically disabled after tamper detection and until the system acknowledges the tamper. Disabling the prescaler after detecting a tamper event conserves power and freezes the state of the active tamper outputs and glitch filters. To ensure a clean transition, the prescaler is disabled at the end of a 1 Hz period.

uint32_t prescaler

Initial value for the TDET prescaler 15-bit value.

struct __tdet__pin__config

#include <fsl_tdet.h> TDET Tamper Pin configuration registers.

This structure defines values for TDET Pin Direction, Pin Polarity, and Glitch Filter registers.

Public Members

enum *_tdet_pin_polarity* pinPolarity

Selects tamper pin expected value

enum *_tdet_pin_direction* pinDirection

Selects tamper pin direction

bool tamperPullEnable

Enable/disable pull resistor on the tamper pin

enum *_tdet_glitch_filter_sample_freq* tamperPinSampleFrequency

Selects tamper pin sample frequency

enum *_tdet_glitch_filter_sample_width* tamperPinSampleWidth

Selects tamper pin sample width

bool glitchFilterEnable

Enable/disable glitch filter on the tamper pin

enum *_tdet_glitch_filter_prescaler* glitchFilterPrescaler

Selects the prescaler for the glitch filter on tamper pin

uint8_t glitchFilterWidth

6-bit value to configure number of clock edges the input must remain stable for to be passed through the glitch filter for the tamper pin

enum *_tdet_glitch_filter_expected* tamperPinExpected

Selects tamper pin expected value

enum *_tdet_glitch_filter_pull* tamperPullSelect

Selects the direction of the tamper pin pull resistor

struct __tdet_active_tamper_config

#include <fsl_tdet.h> TDET Active Tamper registers.

This structure defines values for TDET Active Tamper Registers.

Public Members

uint32_t activeTamperShift

Active tamper shift register. initialize to non-zero value.

uint32_t activeTamperPolynomial

Polynomial of the active tamper shift register.

2.74 TRDC: Trusted Resource Domain Controller

void TRDC_Init(TRDC_Type *base)

Initializes the TRDC module.

This function enables the TRDC clock.

Parameters

- base – TRDC peripheral base address.

void TRDC_Deinit(TRDC_Type *base)

De-initializes the TRDC module.

This function disables the TRDC clock.

Parameters

- base – TRDC peripheral base address.

static inline uint8_t TRDC_GetCurrentMasterDomainId(TRDC_Type *base)

Gets the domain ID of the current bus master.

Parameters

- base – TRDC peripheral base address.

Returns

Domain ID of current bus master.

void TRDC_GetHardwareConfig(TRDC_Type *base, *trdc_hardware_config_t* *config)

Gets the TRDC hardware configuration.

This function gets the TRDC hardware configurations, including number of bus masters, number of domains, number of MRCs and number of PACs.

Parameters

- base – TRDC peripheral base address.
- config – Pointer to the structure to get the configuration.

static inline void TRDC_SetDacGlobalValid(TRDC_Type *base)

Sets the TRDC DAC(Domain Assignment Controllers) global valid.

Once enabled, it will remain enabled until next reset.

Parameters

- base – TRDC peripheral base address.

static inline void TRDC_LockMasterDomainAssignment(TRDC_Type *base, uint8_t master, uint8_t regNum)

Locks the bus master domain assignment register.

This function locks the master domain assignment. After it is locked, the register can't be changed until next reset.

Parameters

- base – TRDC peripheral base address.
- master – Which master to configure, refer to trdcx_master_t in processor header file, x is trdc instance.
- regNum – Which register to configure, processor master can have more than one register for the MDAC configuration.
- assignIndex – Which assignment register to lock.

static inline void TRDC_SetMasterDomainAssignmentValid(TRDC_Type *base, uint8_t master, uint8_t regNum, bool valid)

Sets the master domain assignment as valid or invalid.

This function sets the master domain assignment as valid or invalid.

Parameters

- base – TRDC peripheral base address.
- master – Which master to configure.
- regNum – Which register to configure, processor master can have more than one register for the MDAC configuration.
- assignIndex – Index for the domain assignment register.
- valid – True to set valid, false to set invalid.

void TRDC_GetDefaultProcessorDomainAssignment(*trdc_processor_domain_assignment_t* *domainAssignment)

Gets the default master domain assignment for the processor bus master.

This function gets the default master domain assignment for the processor bus master. It should only be used for the processor bus masters, such as CORE0. This function sets the assignment as follows:

```
assignment->domainId         = 0U;
assignment->domainIdSelect   = kTRDC_DidMda;
assignment->lock             = 0U;
```

Parameters

- domainAssignment – Pointer to the assignment structure.

void TRDC_GetDefaultNonProcessorDomainAssignment(*trdc_non_processor_domain_assignment_t* *domainAssignment)

Gets the default master domain assignment for non-processor bus master.

This function gets the default master domain assignment for non-processor bus master. It should only be used for the non-processor bus masters, such as DMA. This function sets the assignment as follows:

```
assignment->domainId         = 0U;
assignment->privilegeAttr    = kTRDC_ForceUser;
assignment->secureAttr       = kTRDC_ForceSecure;
assignment->bypassDomainId   = 0U;
assignment->lock             = 0U;
```

Parameters

- domainAssignment – Pointer to the assignment structure.

void TRDC_SetProcessorDomainAssignment(TRDC_Type *base, uint8_t master, uint8_t regNum, const *trdc_processor_domain_assignment_t* *domainAssignment)

Sets the processor bus master domain assignment.

This function sets the processor master domain assignment as valid. One bus master might have multiple domain assignment registers. The parameter assignIndex specifies which assignment register to set.

Example: Set domain assignment for core 0.

```
trdc_processor_domain_assignment_t processorAssignment;

TRDC_GetDefaultProcessorDomainAssignment(&processorAssignment);

processorAssignment.domainId = 0;
processorAssignment.xxx      = xxx;
TRDC_SetMasterDomainAssignment(TRDC, &processorAssignment);
```

Parameters

- base – TRDC peripheral base address.
- master – Which master to configure, refer to trdc_master_t in processor header file.
- regNum – Which register to configure, processor master can have more than one register for the MDAC configuration.
- domainAssignment – Pointer to the assignment structure.

void TRDC_SetNonProcessorDomainAssignment(TRDC_Type *base, uint8_t master, const *trdc_non_processor_domain_assignment_t* *domainAssignment)

Sets the non-processor bus master domain assignment.

This function sets the non-processor master domain assignment as valid. One bus master might have multiple domain assignment registers. The parameter assignIndex specifies which assignment register to set.

Example: Set domain assignment for DMA0.

```
trdc_non_processor_domain_assignment_t nonProcessorAssignment;

TRDC_GetDefaultNonProcessorDomainAssignment(&nonProcessorAssignment);
nonProcessorAssignment.domainId = 1;
```

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```
nonProcessorAssignment.xxx      = xxx;

TRDC_SetMasterDomainAssignment(TRDC, kTrdcMasterDma0, 0U, &nonProcessorAssignment);
```

Parameters

- base – TRDC peripheral base address.
- master – Which master to configure, refer to trdc_master_t in processor header file.
- domainAssignment – Pointer to the assignment structure.

static inline uint64_t TRDC_GetActiveMasterPidMap(TRDC_Type *base)

Gets the bit map of the bus master(s) that is(are) sourcing a PID register.

This function sets the non-processor master domain assignment as valid.

Parameters

- base – TRDC peripheral base address.

Returns

the bit map of the master(s). Bit 1 sets indicates bus master 1.

void TRDC_SetPid(TRDC_Type *base, uint8_t master, const *trdc_pid_config_t* *pidConfig)

Sets the current Process identifier(PID) for processor core.

Each processor has a corresponding process identifier (PID) which can be used to group tasks into different domains. Secure privileged software saves and restores the PID as part of any context switch. This data structure defines an array of 32-bit values, one per MDA module, that define the PID. Since this register resource is only applicable to processor cores, the data structure is typically sparsely populated. The HWCFG[2-3] registers provide a bitmap of the implemented PIDn registers. This data structure is indexed using the corresponding MDA instance number. Depending on the operating clock domain of each DAC instance, there may be optional information stored in the corresponding PIDm register to properly implement the LK2 = 2 functionality.

Parameters

- base – TRDC peripheral base address.
- master – Which processor master to configure, refer to trdc_master_t in processor header file.
- pidConfig – Pointer to the configuration structure.

void TRDC_GetDefaultIDAUConfig(*trdc_idau_config_t* *idauConfiguration)

Gets the default IDAU(Implementation-Defined Attribution Unit) configuration.

```
config->lockSecureVTOR    = false;
config->lockNonsecureVTOR = false;
config->lockSecureMPU     = false;
config->lockNonsecureMPU  = false;
config->lockSAU           = false;
```

Parameters

- domainAssignment – Pointer to the configuration structure.

void TRDC_SetIDAU(TRDC_Type *base, const *trdc_idau_config_t* *idauConfiguration)

Sets the IDAU(Implementation-Defined Attribution Unit) control configuration.

Example: Lock the secure and non-secure MPU registers.

```
trdc_idau_config_t idauConfiguration;

TRDC_GetDefaultIDAUConfig(&idauConfiguration);

idauConfiguration.lockSecureMPU = true;
idauConfiguration.lockNonsecureMPU      = true;
TRDC_SetIDAU(TRDC, &idauConfiguration);
```

Parameters

- base – TRDC peripheral base address.
- domainAssignment – Pointer to the configuration structure.

static inline void TRDC_EnableFlashLogicalWindow(TRDC_Type *base, bool enable)

Enables/disables the FLW(flash logical window) function.

Parameters

- base – TRDC peripheral base address.
- enable – True to enable, false to disable.

static inline void TRDC_LockFlashLogicalWindow(TRDC_Type *base)

Locks FLW registers. Once locked the registers can noy be updated until next reset.

Parameters

- base – TRDC peripheral base address.

static inline uint32_t TRDC_GetFlashLogicalWindowPbase(TRDC_Type *base)

Gets the FLW physical base address.

Parameters

- base – TRDC peripheral base address.

Returns

Physical address of the FLW function.

static inline void TRDC_GetSetFlashLogicalWindowSize(TRDC_Type *base, uint16_t size)

Sets the FLW size.

Parameters

- base – TRDC peripheral base address.
- size – Size of the FLW in unit of 32k bytes.

void TRDC_GetDefaultFlashLogicalWindowConfig(*trdc_flw_config_t* *flwConfiguration)

Gets the default FLW(Flsh Logical Window) configuration.

```
config->blockCount    = false;
config->arrayBaseAddr = false;
config->lock      = false;
config->enable    = false;
```

Parameters

- flwConfiguration – Pointer to the configuration structure.

void TRDC_SetFlashLogicalWindow(TRDC_Type *base, const *trdc_flw_config_t* *flwConfiguration)

Sets the FLW function's configuration.

```
trdc_flw_config_t flwConfiguration;

TRDC_GetDefaultIDAUConfig(&flwConfiguration);

flwConfiguration.blockCount = 32U;
flwConfiguration.arrayBaseAddr = 0xXXXXXXXX;
TRDC_SetIDAU(TRDC, &flwConfiguration);
```

Parameters

- base – TRDC peripheral base address.
- flwConfiguration – Pointer to the configuration structure.

status_t TRDC_GetAndClearFirstDomainError(TRDC_Type *base, *trdc_domain_error_t* *error)

Gets and clears the first domain error of the current domain.

This function gets the first access violation information for the current domain and clears the pending flag. There might be multiple access violations pending for the current domain. This function only processes the first error.

Parameters

- base – TRDC peripheral base address.
- error – Pointer to the error information.

Returns

If the access violation is captured, this function returns the kStatus_Success. The error information can be obtained from the parameter error. If no access violation is captured, this function returns the kStatus_NoData.

status_t TRDC_GetAndClearFirstSpecificDomainError(TRDC_Type *base, *trdc_domain_error_t* *error, uint8_t domainId)

Gets and clears the first domain error of the specific domain.

This function gets the first access violation information for the specific domain and clears the pending flag. There might be multiple access violations pending for the current domain. This function only processes the first error.

Parameters

- base – TRDC peripheral base address.
- error – Pointer to the error information.
- domainId – The error of which domain to get and clear.

Returns

If the access violation is captured, this function returns the kStatus_Success. The error information can be obtained from the parameter error. If no access violation is captured, this function returns the kStatus_NoData.

static inline void TRDC_SetMrcGlobalValid(TRDC_Type *base)

Sets the TRDC MRC(Memory Region Checkers) global valid.

Once enabled, it will remain enabled until next reset.

Parameters

- base – TRDC peripheral base address.

static inline uint8_t TRDC_GetMrcRegionNumber(TRDC_Type *base, uint8_t mrcIdx)

Gets the TRDC MRC(Memory Region Checkers) region number valid.

Parameters

- base – TRDC peripheral base address.

Returns
the region number of the given MRC instance

void TRDC_MrcSetMemoryAccessConfig(TRDC_Type *base, const *trdc_memory_access_control_config_t* *config, uint8_t mrcIdx, uint8_t regIdx)

Sets the memory access configuration for one of the access control register of one MRC.

Example: Enable the secure operations and lock the configuration for MRC0 region 1.

```
trdc_memory_access_control_config_t config;

config.securePrivX = true;
config.securePrivW = true;
config.securePrivR = true;
config.lock = true;
TRDC_SetMrcMemoryAccess(TRDC, &config, 0, 1);
```

Parameters

- base – TRDC peripheral base address.
- config – Pointer to the configuration structure.
- mrcIdx – MRC index.
- regIdx – Register number.

void TRDC_MrcEnableDomainNseUpdate(TRDC_Type *base, uint8_t mrcIdx, uint16_t domianMask, bool enable)

Enables the update of the selected domians.

After the domians' update are enabled, their regions' NSE bits can be set or clear.

Parameters

- base – TRDC peripheral base address.
- mrcIdx – MRC index.
- domianMask – Bit mask of the domains to be enabled.
- enable – True to enable, false to disable.

void TRDC_MrcRegionNseSet(TRDC_Type *base, uint8_t mrcIdx, uint16_t regionMask)

Sets the NSE bits of the selected regions for domains.

This function sets the NSE bits for the selected regions for the domains whose update are enabled.

Parameters

- base – TRDC peripheral base address.
- mrcIdx – MRC index.
- regionMask – Bit mask of the regions whose NSE bits to set.

void TRDC_MrcRegionNseClear(TRDC_Type *base, uint8_t mrcIdx, uint16_t regionMask)

Clears the NSE bits of the selected regions for domains.

This function clears the NSE bits for the selected regions for the domains whose update are enabled.

Parameters

- base – TRDC peripheral base address.

- mrcIdx – MRC index.
- regionMask – Bit mask of the regions whose NSE bits to clear.

void TRDC_MrcDomainNseClear(TRDC_Type *base, uint8_t mrcIdx, uint16_t domainMask)

Clears the NSE bits for all the regions of the selected domains.

This function clears the NSE bits for all regions of selected domains whose update are enabled.

Parameters

- base – TRDC peripheral base address.
- mrcIdx – MRC index.
- domainMask – Bit mask of the domians whose NSE bits to clear.

void TRDC_MrcSetRegionDescriptorConfig(TRDC_Type *base, const *trdc_mrc_region_descriptor_config_t* *config)

Sets the configuration for one of the region descriptor per domain per MRC instnce.

This function sets the configuration for one of the region descriptor, including the start and end address of the region, memory access control policy and valid.

Parameters

- base – TRDC peripheral base address.
- config – Pointer to region descriptor configuration structure.

static inline void TRDC_SetMbcGlobalValid(TRDC_Type *base)

Sets the TRDC MBC(Memory Block Checkers) global valid.

Once enabled, it will remain enabled until next reset.

Parameters

- base – TRDC peripheral base address.

void TRDC_GetMbcHardwareConfig(TRDC_Type *base, *trdc_slave_memory_hardware_config_t* *config, uint8_t mbcIdx, uint8_t slvIdx)

Gets the hardware configuration of the one of two slave memories within each MBC(memory block checker).

Parameters

- base – TRDC peripheral base address.
- config – Pointer to the structure to get the configuration.
- mbcIdx – MBC number.
- slvIdx – Slave number.

void TRDC_MbcSetNseUpdateConfig(TRDC_Type *base, const *trdc_mbc_nse_update_config_t* *config, uint8_t mbcIdx)

Sets the NSR update configuration for one of the MBC instance.

After set the NSE configuration, the configured memory area can be updateby NSE set/clear.

Parameters

- base – TRDC peripheral base address.
- config – Pointer to NSE update configuration structure.
- mbcIdx – MBC index.

void TRDC_MbcWordNseSet(TRDC_Type *base, uint8_t mbcIdx, uint32_t bitMask)

Sets the NSE bits of the selected configuration words according to NSE update configuration.

This function sets the NSE bits of the word for the configured regio, memory.

Parameters

- base – TRDC peripheral base address.
- mbcIdx – MBC index.
- bitMask – Mask of the bits whose NSE bits to set.

void TRDC_MbcWordNseClear(TRDC_Type *base, uint8_t mbcIdx, uint32_t bitMask)

Clears the NSE bits of the selected configuration words according to NSE update configuration.

This function sets the NSE bits of the word for the configured regio, memory.

Parameters

- base – TRDC peripheral base address.
- mbcIdx – MBC index.
- bitMask – Mask of the bits whose NSE bits to clear.

void TRDC_MbcNseClearAll(TRDC_Type *base, uint8_t mbcIdx, uint16_t domainMask, uint8_t slave)

Clears all configuration words' NSE bits of the selected domain and memory.

Parameters

- base – TRDC peripheral base address.
- mbcIdx – MBC index.
- domainMask – Mask of the domains whose NSE bits to clear, 0b110 means clear domain 1&2.
- slaveMask – Mask of the slaves whose NSE bits to clear, 0x11 means clear all slave 0&1's NSE bits.

void TRDC_MbcSetMemoryAccessConfig(TRDC_Type *base, const *trdc_memory_access_control_config_t* *config, uint8_t mbcIdx, uint8_t rgdIdx)

Sets the memory access configuration for one of the region descriptor of one MBC.

Example: Enable the secure operations and lock the configuration for MRC0 region 1.

```
trdc_memory_access_control_config_t config;

config.securePrivX = true;
config.securePrivW = true;
config.securePrivR = true;
config.lock = true;
TRDC_SetMbcMemoryAccess(TRDC, &config, 0, 1);
```

Parameters

- base – TRDC peripheral base address.
- config – Pointer to the configuration structure.
- mbcIdx – MBC index.
- rgdIdx – Region descriptor number.

void TRDC_MbcSetMemoryBlockConfig(TRDC_Type *base, const *trdc_mbc_memory_block_config_t* *config)

Sets the configuration for one of the memory block per domain per MBC instnce.

This function sets the configuration for one of the memory block, including the memory access control policy and nse enable.

Parameters

- base – TRDC peripheral base address.
- config – Pointer to memory block configuration structure.

enum _trdc_did_sel

TRDC domain ID select method, the register bit TRDC_MDA_W0_0_DFMT0[DIDS], used for domain hit evaluation.

Values:

enumerator kTRDC_DidMda

Use MDAn[2:0] as DID.

enumerator kTRDC_DidInput

Use the input DID (DID_in) as DID.

enumerator kTRDC_DidMdaAndInput

Use MDAn[2] concatenated with DID_in[1:0] as DID.

enumerator kTRDC_DidReserved

Reserved.

enum _trdc_secure_attr

TRDC secure attribute, the register bit TRDC_MDA_W0_0_DFMT0[SA], used for bus master domain assignment.

Values:

enumerator kTRDC_ForceSecure

Force the bus attribute for this master to secure.

enumerator kTRDC_ForceNonSecure

Force the bus attribute for this master to non-secure.

enumerator kTRDC_MasterSecure

Use the bus master's secure/nonsecure attribute directly.

enumerator kTRDC_MasterSecure1

Use the bus master's secure/nonsecure attribute directly.

enum _trdc_pid_domain_hit_config

The configuration of domain hit evaluation of PID.

Values:

enumerator kTRDC_pidDomainHitNone0

No PID is included in the domain hit evaluation.

enumerator kTRDC_pidDomainHitNone1

No PID is included in the domain hit evaluation.

enumerator kTRDC_pidDomainHitInclusive

The PID is included in the domain hit evaluation when (PID & ~PIDM).

enumerator kTRDC_pidDomainHitExclusive

The PID is included in the domain hit evaluation when ~(PID & ~PIDM).

enum _trdc_privilege_attr

TRDC privileged attribute, the register bit TRDC_MDA_W0_x_DFMT1[PA], used for non-processor bus master domain assignment.

Values:

enumerator kTRDC_ForceUser

Force the bus attribute for this master to user.

enumerator kTRDC_ForcePrivilege

Force the bus attribute for this master to privileged.

enumerator kTRDC_MasterPrivilege

Use the bus master's attribute directly.

enumerator kTRDC_MasterPrivilege1

Use the bus master's attribute directly.

enum _trdc_pid_lock

PID lock configuration.

Values:

enumerator kTRDC_PidUnlocked0

The PID value can be updated by any secure priviledged write.

enumerator kTRDC_PidUnlocked1

The PID value can be updated by any secure priviledged write.

enumerator kTRDC_PidUnlocked2

The PID value can be updated by any secure priviledged write from the bus master that first configured this register.

enumerator kTRDC_PidLocked

The PID value is locked until next reset.

enum _trdc_controller

TRDC controller definition for domain error check. Each TRDC instance may have different MRC or MBC count, call TRDC_GetHardwareConfig to get the actual count.

Values:

enumerator kTRDC_MemBlockController0
Memory block checker 0.

enumerator kTRDC_MemBlockController1
Memory block checker 1.

enumerator kTRDC_MemBlockController2
Memory block checker 2.

enumerator kTRDC_MemBlockController3
Memory block checker 3.

enumerator kTRDC_MemRegionChecker0
Memory region checker 0.

enumerator kTRDC_MemRegionChecker1
Memory region checker 1.

enumerator kTRDC_MemRegionChecker2
Memory region checker 2.

enumerator kTRDC_MemRegionChecker3
Memory region checker 3.

enumerator kTRDC_MemRegionChecker4
Memory region checker 4.

enumerator kTRDC_MemRegionChecker5
Memory region checker 5.

enumerator kTRDC_MemRegionChecker6
Memory region checker 6.

enum __trdc_error_state
TRDC domain error state definition TRDC_MBCn_DERR_W1[EST] or TRDC_MRCn_DERR_W1[EST].

Values:

enumerator kTRDC_ErrorStateNone
No access violation detected.

enumerator kTRDC_ErrorStateNone1
No access violation detected.

enumerator kTRDC_ErrorStateSingle
Single access violation detected.

enumerator kTRDC_ErrorStateMulti

Multiple access violation detected.

enum _trdc_error_attr

TRDC domain error attribute definition TRDC_MBCn_DERR_W1[EATR] or TRDC_MRCn_DERR_W1[EATR].

Values:

enumerator kTRDC_ErrorSecureUserInst

Secure user mode, instruction fetch access.

enumerator kTRDC_ErrorSecureUserData

Secure user mode, data access.

enumerator kTRDC_ErrorSecurePrivilegeInst

Secure privileged mode, instruction fetch access.

enumerator kTRDC_ErrorSecurePrivilegeData

Secure privileged mode, data access.

enumerator kTRDC_ErrorNonSecureUserInst

NonSecure user mode, instruction fetch access.

enumerator kTRDC_ErrorNonSecureUserData

NonSecure user mode, data access.

enumerator kTRDC_ErrorNonSecurePrivilegeInst

NonSecure privileged mode, instruction fetch access.

enumerator kTRDC_ErrorNonSecurePrivilegeData

NonSecure privileged mode, data access.

enum _trdc_error_type

TRDC domain error access type definition TRDC_DERR_W1_n[ERW].

Values:

enumerator kTRDC_ErrorTypeRead

Error occurs on read reference.

enumerator kTRDC_ErrorTypeWrite

Error occurs on write reference.

enum _trdc_region_descriptor

The region descriptor enumeration, used to form a mask to set/clear the NSE bits for one or several regions.

Values:

enumerator kTRDC_RegionDescriptor0
Region descriptor 0.

enumerator kTRDC_RegionDescriptor1
Region descriptor 1.

enumerator kTRDC_RegionDescriptor2
Region descriptor 2.

enumerator kTRDC_RegionDescriptor3
Region descriptor 3.

enumerator kTRDC_RegionDescriptor4
Region descriptor 4.

enumerator kTRDC_RegionDescriptor5
Region descriptor 5.

enumerator kTRDC_RegionDescriptor6
Region descriptor 6.

enumerator kTRDC_RegionDescriptor7
Region descriptor 7.

enumerator kTRDC_RegionDescriptor8
Region descriptor 8.

enumerator kTRDC_RegionDescriptor9
Region descriptor 9.

enumerator kTRDC_RegionDescriptor10
Region descriptor 10.

enumerator kTRDC_RegionDescriptor11
Region descriptor 11.

enumerator kTRDC_RegionDescriptor12
Region descriptor 12.

enumerator kTRDC_RegionDescriptor13
Region descriptor 13.

enumerator kTRDC_RegionDescriptor14
Region descriptor 14.

enumerator kTRDC_RegionDescriptor15
Region descriptor 15.

enum _trdc_MRC_domain

The MRC domain enumeration, used to form a mask to enable/disable the update or clear all NSE bits of one or several domains.

Values:

enumerator kTRDC_MrcDomain0
Domain 0.

enumerator kTRDC_MrcDomain1
Domain 1.

enumerator kTRDC_MrcDomain2
Domain 2.

enumerator kTRDC_MrcDomain3
Domain 3.

enumerator kTRDC_MrcDomain4
Domain 4.

enumerator kTRDC_MrcDomain5
Domain 5.

enumerator kTRDC_MrcDomain6
Domain 6.

enumerator kTRDC_MrcDomain7
Domain 7.

enumerator kTRDC_MrcDomain8
Domain 8.

enumerator kTRDC_MrcDomain9
Domain 9.

enumerator kTRDC_MrcDomain10
Domain 10.

enumerator kTRDC_MrcDomain11
Domain 11.

enumerator kTRDC_MrcDomain12
Domain 12.

enumerator kTRDC_MrcDomain13
Domain 13.

enumerator kTRDC_MrcDomain14
Domain 14.

enumerator kTRDC_MrcDomain15
Domain 15.

enum _trdc_MBC_domain
The MBC domain enumeration, used to form a mask to enable/disable the update or clear NSE bits of one or several domains.

Values:

enumerator kTRDC_MbcDomain0
Domain 0.

enumerator kTRDC_MbcDomain1
Domain 1.

enumerator kTRDC_MbcDomain2
Domain 2.

enumerator kTRDC_MbcDomain3
Domain 3.

enumerator kTRDC_MbcDomain4
Domain 4.

enumerator kTRDC_MbcDomain5
Domain 5.

enumerator kTRDC_MbcDomain6
Domain 6.

enumerator kTRDC_MbcDomain7
Domain 7.

enum _trdc_MBC_memory
The MBC slave memory enumeration, used to form a mask to enable/disable the update or clear NSE bits of one or several memory block.

Values:

enumerator kTRDC_MbcSlaveMemory0
Memory 0.

enumerator kTRDC_MbcSlaveMemory1
Memory 1.

enumerator kTRDC_MbcSlaveMemory2
Memory 2.

enumerator kTRDC_MbcSlaveMemory3
Memory 3.

enum _trdc_MBC_bit

The MBC bit enumeration, used to form a mask to set/clear configured words' NSE.

Values:

enumerator kTRDC_MbcBit0
Bit 0.

enumerator kTRDC_MbcBit1
Bit 1.

enumerator kTRDC_MbcBit2
Bit 2.

enumerator kTRDC_MbcBit3
Bit 3.

enumerator kTRDC_MbcBit4
Bit 4.

enumerator kTRDC_MbcBit5
Bit 5.

enumerator kTRDC_MbcBit6
Bit 6.

enumerator kTRDC_MbcBit7
Bit 7.

enumerator kTRDC_MbcBit8
Bit 8.

enumerator kTRDC_MbcBit9
Bit 9.

enumerator kTRDC_MbcBit10
Bit 10.

enumerator kTRDC_MbcBit11
Bit 11.

enumerator kTRDC_MbcBit12
Bit 12.

enumerator kTRDC_MbcBit13
Bit 13.

enumerator kTRDC_MbcBit14
Bit 14.

enumerator kTRDC_MbcBit15
Bit 15.

enumerator kTRDC_MbcBit16
Bit 16.

enumerator kTRDC_MbcBit17
Bit 17.

enumerator kTRDC_MbcBit18
Bit 18.

enumerator kTRDC_MbcBit19
Bit 19.

enumerator kTRDC_MbcBit20
Bit 20.

enumerator kTRDC_MbcBit21
Bit 21.

enumerator kTRDC_MbcBit22
Bit 22.

enumerator kTRDC_MbcBit23
Bit 23.

enumerator kTRDC_MbcBit24
Bit 24.

enumerator kTRDC_MbcBit25
Bit 25.

enumerator kTRDC_MbcBit26
Bit 26.

enumerator kTRDC_MbcBit27
Bit 27.

enumerator kTRDC_MbcBit28
Bit 28.

enumerator kTRDC_MbcBit29
Bit 29.

enumerator kTRDC_MbcBit30
Bit 30.

enumerator kTRDC_MbcBit31

Bit 31.

typedef struct *_trdc_hardware_config* trdc_hardware_config_t

TRDC hardware configuration.

typedef struct *_trdc_slave_memory_hardware_config* trdc_slave_memory_hardware_config_t

Hardware configuration of the two slave memories within each MBC(memory block checker).

typedef enum *_trdc_did_sel* trdc_did_sel_t

TRDC domain ID select method, the register bit TRDC_MDA_W0_0_DFMT0[DIDS], used for domain hit evaluation.

typedef enum *_trdc_secure_attr* trdc_secure_attr_t

TRDC secure attribute, the register bit TRDC_MDA_W0_0_DFMT0[SA], used for bus master domain assignment.

typedef enum *_trdc_pid_domain_hit_config* trdc_pid_domain_hit_config_t

The configuration of domain hit evaluation of PID.

typedef struct *_trdc_processor_domain_assignment* trdc_processor_domain_assignment_t

Domain assignment for the processor bus master.

typedef enum *_trdc_privilege_attr* trdc_privilege_attr_t

TRDC privileged attribute, the register bit TRDC_MDA_W0_x_DFMT1[PA], used for non-processor bus master domain assignment.

typedef struct *_trdc_non_processor_domain_assignment*
trdc_non_processor_domain_assignment_t

Domain assignment for the non-processor bus master.

typedef enum *_trdc_pid_lock* trdc_pid_lock_t

PID lock configuration.

typedef struct *_trdc_pid_config* trdc_pid_config_t

Process identifier(PID) configuration for processor cores.

typedef struct *_trdc_idau_config* trdc_idau_config_t

IDAU(Implementation-Defined Attribution Unit) configuration for TZ-M function control.

typedef struct *_trdc_flw_config* trdc_flw_config_t

FLW(Flash Logical Window) configuration.

typedef enum *_trdc_controller* trdc_controller_t

TRDC controller definition for domain error check. Each TRDC instance may have different MRC or MBC count, call TRDC_GetHardwareConfig to get the actual count.

typedef enum *_trdc_error_state* trdc_error_state_t

TRDC domain error state definition TRDC_MBCn_DERR_W1[EST] or TRDC_MRCn_DERR_W1[EST].

typedef enum *_trdc_error_attr* trdc_error_attr_t

TRDC domain error attribute definition TRDC_MBCn_DERR_W1[EATR] or TRDC_MRCn_DERR_W1[EATR].

typedef enum *_trdc_error_type* trdc_error_type_t

TRDC domain error access type definition TRDC_DERR_W1_n[ERW].

typedef struct *_trdc_domain_error* trdc_domain_error_t

TRDC domain error definition.

typedef struct *_trdc_memory_access_control_config* trdc_memory_access_control_config_t

Memory access control configuration for MBC/MRC.

typedef struct *_trdc_mrc_region_descriptor_config* trdc_mrc_region_descriptor_config_t

The configuration of each region descriptor per domain per MRC instance.

typedef struct *_trdc_mbc_nse_update_config* trdc_mbc_nse_update_config_t

The configuration of MBC NSE update.

typedef struct *_trdc_mbc_memory_block_config* trdc_mbc_memory_block_config_t

The configuration of each memory block per domain per MBC instance.

FSL_TRDC_DRIVER_VERSION

struct _trdc_hardware_config

#include <fsl_trdc.h> TRDC hardware configuration.

Public Members

uint8_t masterNumber

Number of bus masters.

uint8_t domainNumber

Number of domains.

uint8_t mbcNumber

Number of MBCs.

uint8_t mrcNumber

Number of MRCs.

struct _trdc_slave_memory_hardware_config

#include <fsl_trdc.h> Hardware configuration of the two slave memories within each MBC(memory block checker).

Public Members

uint32_t blockNum
Number of blocks.

uint32_t blockSize
Block size.

struct __trdc__processor__domain__assignment
#include <fsl_trdc.h> Domain assignment for the processor bus master.

Public Members

uint32_t domainId
Domain ID.

uint32_t domainIdSelect
Domain ID select method, see *trdc_did_sel_t*.

uint32_t pidDomainHitConfig
The configuration of the domain hit evaluation for PID, see *trdc_pid_domain_hit_config_t*.

uint32_t pidMask
The mask combined with PID, so multiple PID can be included as part of the domain hit determination. Set to 0 to disable.

uint32_t secureAttr
Secure attribute, see *trdc_secure_attr_t*.

uint32_t pid
The process identifier, combined with pidMask to form the domain hit determination.

uint32_t ___pad0___
Reserved.

uint32_t lock
Lock the register.

uint32_t ___pad1___
Reserved.

struct __trdc__non__processor__domain__assignment
#include <fsl_trdc.h> Domain assignment for the non-processor bus master.

Public Members

uint32_t domainId
: Domain ID.

uint32_t privilegeAttr
: Privileged attribute, see *trdc_privilege_attr_t*.

uint32_t secureAttr
: Secure attribute, see *trdc_secure_attr_t*.

uint32_t bypassDomainId
: Bypass domain ID.

uint32_t ___pad0___
: Reserved.

uint32_t lock
: Lock the register.

uint32_t ___pad1___
: Reserved.

struct __trdc__pid__config
: *#include <fsl_trdc.h>* Process identifier(PID) configuration for processor cores.

Public Members

uint32_t pid
: The process identifier of the executing task. The highest bit can be used to define secure/nonsecure attribute of the task.

uint32_t ___pad0___
: Reserved.

uint32_t lock
: How to lock the register, see *trdc_pid_lock_t*.

uint32_t ___pad1___
: Reserved.

struct __trdc__idau__config
: *#include <fsl_trdc.h>* IDAU(Implementation-Defined Attribution Unit) configuration for TZ-M function control.

Public Members

uint32_t ___pad0___
: Reserved.

uint32_t lockSecureVTOR
: Disable writes to secure VTOR(Vector Table Offset Register).

uint32_t lockNonsecureVTOR
: Disable writes to non-secure VTOR, Application interrupt and Reset Control Registers.

uint32_t lockSecureMPU
: Disable writes to secure MPU(Memory Protection Unit) from software or from a debug agent connected to the processor in Secure state.

uint32_t lockNonsecureMPU
: Disable writes to non-secure MPU(Memory Protection Unit) from software or from a debug agent connected to the processor.

uint32_t lockSAU
: Disable writes to SAU(Security Attribution Unit) registers.

uint32_t ___pad1___
: Reserved.

struct __trdc__flw__config
: *#include <fsl_trdc.h>* FLW(Flash Logical Window) configuration.

Public Members

uint16_t blockCount
: Block count of the Flash Logic Window in 32KByte blocks.

uint32_t arrayBaseAddr
: Flash array base address of the Flash Logical Window.

bool lock
: Disable writes to FLW registers.

bool enable
: Enable FLW function.

struct __trdc__domain__error
: *#include <fsl_trdc.h>* TRDC domain error definition.

Public Members

trdc_controller_t controller
: Which controller captured access violation.

uint32_t address
: Access address that generated access violation.

trdc_error_state_t errorState
Error state.

trdc_error_attr_t errorAttr
Error attribute.

trdc_error_type_t errorType
Error type.

uint8_t errorPort
Error port.

uint8_t domainId
Domain ID.

uint8_t slaveMemoryIdx
The slave memory index. Only apply when violation in MBC.

struct __trdc_memory_access_control_config
#include <fsl_trdc.h> Memory access control configuration for MBC/MRC.

Public Members

uint32_t nonsecureUsrX
Allow nonsecure user execute access.

uint32_t nonsecureUsrW
Allow nonsecure user write access.

uint32_t nonsecureUsrR
Allow nonsecure user read access.

uint32_t ___pad0___
Reserved.

uint32_t nonsecurePrivX
Allow nonsecure privilege execute access.

uint32_t nonsecurePrivW
Allow nonsecure privilege write access.

uint32_t nonsecurePrivR
Allow nonsecure privilege read access.

uint32_t ___pad1___
Reserved.

uint32_t secureUsrX
: Allow secure user execute access.

uint32_t secureUsrW
: Allow secure user write access.

uint32_t secureUsrR
: Allow secure user read access.

uint32_t ___pad2___
: Reserved.

uint32_t securePrivX
: Allownsecure privilege execute access.

uint32_t securePrivW
: Allownsecure privilege write access.

uint32_t securePrivR
: Allownsecure privilege read access.

uint32_t ___pad3___
: Reserved.

uint32_t lock
: Lock the configuration until next reset, only apply to access control register 0.

struct __trdc__mrc__region__descriptor__config
: *#include <fsl_trdc.h>* The configuration of each region descriptor per domain per MRC instance.

Public Members

uint8_t memoryAccessControlSelect
: Select one of the 8 access control policies for this region, for access cotrol policies see *trdc_memory_access_control_config_t*.

uint32_t startAddr
: Physical start address.

bool valid
: Lock the register.

bool nseEnable
: Enable non-secure accesses and disable secure accesses.

uint32_t endAddr
: Physical start address.

uint8_t mrcIdx
: The index of the MRC for this configuration to take effect.

uint8_t domainIdx
: The index of the domain for this configuration to take effect.

uint8_t regionIdx
: The index of the region for this configuration to take effect.

struct __trdc_mbc_nse_update_config
: *#include <fsl_trdc.h>* The configuration of MBC NSE update.

Public Members

uint32_t ___pad0___
: Reserved.

uint32_t wordIdx
: MBC configuration word index to be updated.

uint32_t ___pad1___
: Reserved.

uint32_t memorySelect
: Bit mask of the selected memory to be updated. *_trdc_MBC_memory*.

uint32_t ___pad2___
: Reserved.

uint32_t domianSelect
: Bit mask of the selected domain to be updated. *_trdc_MBC_domain*.

uint32_t ___pad3___
: Reserved.

uint32_t autoIncrement
: Whether to increment the word index after current word is updated using this configuration.

struct __trdc_mbc_memory_block_config
: *#include <fsl_trdc.h>* The configuration of each memory block per domain per MBC instance.

Public Members

uint32_t memoryAccessControlSelect
: Select one of the 8 access control policies for this memory block, for access cotrol policies see *trdc_memory_access_control_config_t*.

uint32_t nseEnable
: Enable non-secure accesses and disable secure accesses.

uint32_t mbcIdx
: The index of the MBC for this configuration to take effect.

uint32_t domainIdx
: The index of the domain for this configuration to take effect.

uint32_t slaveMemoryIdx
: The index of the slave memory for this configuration to take effect.

uint32_t memoryBlockIdx
: The index of the memory block for this configuration to take effect.

2.75 Trdc_core

typedef struct *_TRDC_General_Type* TRDC_General_Type
: TRDC general configuration register definition.

typedef struct *_TRDC_FLW_Type* TRDC_FLW_Type
: TRDC flash logical control register definition.

typedef struct *_TRDC_DomainError_Type* TRDC_DomainError_Type
: TRDC domain error register definition.

typedef struct *_TRDC_DomainAssignment_Type* TRDC_DomainAssignment_Type
: TRDC master domain assignment register definition.

typedef struct *_TRDC_MBC_Type* TRDC_MBC_Type
: TRDC MBC control register definition.

typedef struct *_TRDC_MRC_Type* TRDC_MRC_Type
: TRDC MRC control register definition. MRC_DOM0_RGD_W[region][word].

TRDC_GENERAL_BASE(base)
: TRDC base address convert macro.

TRDC_FLW_BASE(base)

TRDC_DOMAIN_ERROR_BASE(base)

TRDC_DOMAIN_ASSIGNMENT_BASE(base)

TRDC_MBC_BASE(base, instance)

TRDC_MRC_BASE(base, instance)

struct _TRDC_General_Type
: *#include <fsl_trdc_core.h>* TRDC general configuration register definition.

Public Members

___IO uint32_t TRDC_CR
TRDC Register, offset: 0x0

___I uint32_t TRDC_HWCFG0
TRDC Hardware Configuration Register 0, offset: 0xF0

___I uint32_t TRDC_HWCFG1
TRDC Hardware Configuration Register 1, offset: 0xF4

___I uint32_t TRDC_HWCFG2
TRDC Hardware Configuration Register 2, offset: 0xF8

___I uint32_t TRDC_HWCFG3
TRDC Hardware Configuration Register 3, offset: 0xFC

___I uint8_t DACFG [8]
Domain Assignment Configuration Register, array offset: 0x100, array step: 0x1

___IO uint32_t TRDC_IDAU_CR
TRDC IDAU Control Register, offset: 0x1C0

struct _TRDC_FLW_Type
#include <fsl_trdc_core.h> TRDC flash logical control register definition.

Public Members

___IO uint32_t TRDC_FLW_CTL
TRDC FLW Control, offset: 0x1E0

___I uint32_t TRDC_FLW_PBASE
TRDC FLW Physical Base, offset: 0x1E4

___IO uint32_t TRDC_FLW_ABASE
TRDC FLW Array Base, offset: 0x1E8

___IO uint32_t TRDC_FLW_BCNT
TRDC FLW Block Count, offset: 0x1EC

struct _TRDC_DomainError_Type
#include <fsl_trdc_core.h> TRDC domain error register definition.

Public Members

___IO uint32_t TRDC_FDID
TRDC Fault Domain ID, offset: 0x1FC

___I uint32_t TRDC_DERRLOC [16]

TRDC Domain Error Location Register, array offset: 0x200, array step: 0x4

struct _TRDC_DomainAssignment_Type

#include <fsl_trdc_core.h> TRDC master domain assignment register definition.

Public Members

___IO uint32_t PID [8]

Process Identifier, array offset: 0x700, array step: 0x4

struct _TRDC_MBC_Type

#include <fsl_trdc_core.h> TRDC MBC control register definition.

Public Members

___I uint32_t MBC_MEM_GLBCFG [4]

MBC Global Configuration Register, array offset: 0x10000, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_NSE_BLK_INDEX

MBC NonSecure Enable Block Index, array offset: 0x10010, array step: 0x2000

___O uint32_t MBC_NSE_BLK_SET

MBC NonSecure Enable Block Set, array offset: 0x10014, array step: 0x2000

___O uint32_t MBC_NSE_BLK_CLR

MBC NonSecure Enable Block Clear, array offset: 0x10018, array step: 0x2000

___O uint32_t MBC_NSE_BLK_CLR_ALL

MBC NonSecure Enable Block Clear All, array offset: 0x1001C, array step: 0x2000

___IO uint32_t MBC_MEMN_GLBAC [8]

MBC Global Access Control, array offset: 0x10020, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM0_MEM0_BLK_CFG_W [64]

MBC Memory Block Configuration Word, array offset: 0x10040, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM0_MEM0_BLK_NSE_W [16]

MBC Memory Block NonSecure Enable Word, array offset: 0x10140, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM0_MEM1_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x10180, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM0_MEM1_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x101A0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM0_MEM2_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x101A8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM0_MEM2_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x101C8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM0_MEM3_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x101D0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM0_MEM3_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x101F0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM1_MEM0_BLK_CFG_W [64]

MBC Memory Block Configuration Word, array offset: 0x10240, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM1_MEM0_BLK_NSE_W [16]

MBC Memory Block NonSecure Enable Word, array offset: 0x10340, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM1_MEM1_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x10380, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM1_MEM1_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x103A0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM1_MEM2_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x103A8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM1_MEM2_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x103C8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM1_MEM3_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x103D0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM1_MEM3_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x103F0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM2_MEM0_BLK_CFG_W [64]

MBC Memory Block Configuration Word, array offset: 0x10440, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM2_MEM0_BLK_NSE_W [16]

MBC Memory Block NonSecure Enable Word, array offset: 0x10540, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM2_MEM1_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x10580, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM2_MEM1_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x105A0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM2_MEM2_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x105A8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM2_MEM2_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x105C8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM2_MEM3_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x105D0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM2_MEM3_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x105F0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM3_MEM0_BLK_CFG_W [64]

MBC Memory Block Configuration Word, array offset: 0x10640, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM3_MEM0_BLK_NSE_W [16]

MBC Memory Block NonSecure Enable Word, array offset: 0x10740, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM3_MEM1_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x10780, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM3_MEM1_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x107A0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM3_MEM2_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x107A8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM3_MEM2_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x107C8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM3_MEM3_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x107D0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM3_MEM3_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x107F0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM4_MEM0_BLK_CFG_W [64]

MBC Memory Block Configuration Word, array offset: 0x10840, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM4_MEM0_BLK_NSE_W [16]

MBC Memory Block NonSecure Enable Word, array offset: 0x10940, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM4_MEM1_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x10980, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM4_MEM1_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x109A0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM4_MEM2_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x109A8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM4_MEM2_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x109C8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM4_MEM3_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x109D0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM4_MEM3_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x109F0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM5_MEM0_BLK_CFG_W [64]

MBC Memory Block Configuration Word, array offset: 0x10A40, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM5_MEM0_BLK_NSE_W [16]

MBC Memory Block NonSecure Enable Word, array offset: 0x10B40, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM5_MEM1_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x10B80, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM5_MEM1_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x10BA0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM5_MEM2_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x10BA8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM5_MEM2_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x10BC8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM5_MEM3_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x10BD0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM5_MEM3_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x10BF0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM6_MEM0_BLK_CFG_W [64]

MBC Memory Block Configuration Word, array offset: 0x10C40, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM6_MEM0_BLK_NSE_W [16]

MBC Memory Block NonSecure Enable Word, array offset: 0x10D40, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM6_MEM1_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x10D80, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM6_MEM1_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x10DA0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM6_MEM2_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x10DA8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM6_MEM2_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x10DC8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM6_MEM3_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x10DD0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM6_MEM3_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x10DF0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM7_MEM0_BLK_CFG_W [64]

MBC Memory Block Configuration Word, array offset: 0x10E40, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM7_MEM0_BLK_NSE_W [16]

MBC Memory Block NonSecure Enable Word, array offset: 0x10F40, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM7_MEM1_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x10F80, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM7_MEM1_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x10FA0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM7_MEM2_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x10FA8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM7_MEM2_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x10FC8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM7_MEM3_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x10FD0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM7_MEM3_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x10FF0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM8_MEM0_BLK_CFG_W [64]

MBC Memory Block Configuration Word, array offset: 0x11040, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM8_MEM0_BLK_NSE_W [16]

MBC Memory Block NonSecure Enable Word, array offset: 0x11140, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM8_MEM1_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x11180, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM8_MEM1_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x111A0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM8_MEM2_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x111A8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM8_MEM2_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x111C8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM8_MEM3_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x111D0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM8_MEM3_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x111F0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM9_MEM0_BLK_CFG_W [64]

MBC Memory Block Configuration Word, array offset: 0x11240, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM9_MEM0_BLK_NSE_W [16]

MBC Memory Block NonSecure Enable Word, array offset: 0x11340, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM9_MEM1_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x11380, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM9_MEM1_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x113A0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM9_MEM2_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x113A8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM9_MEM2_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x113C8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM9_MEM3_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x113D0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM9_MEM3_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x113F0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM10_MEM0_BLK_CFG_W [64]

MBC Memory Block Configuration Word, array offset: 0x11440, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM10_MEM0_BLK_NSE_W [16]

MBC Memory Block NonSecure Enable Word, array offset: 0x11540, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM10_MEM1_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x11580, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM10_MEM1_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x115A0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM10_MEM2_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x115A8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM10_MEM2_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x115C8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM10_MEM3_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x115D0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM10_MEM3_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x115F0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM11_MEM0_BLK_CFG_W [64]

MBC Memory Block Configuration Word, array offset: 0x11640, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM11_MEM0_BLK_NSE_W [16]

MBC Memory Block NonSecure Enable Word, array offset: 0x11740, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM11_MEM1_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x11780, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM11_MEM1_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x117A0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM11_MEM2_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x117A8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM11_MEM2_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x117C8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM11_MEM3_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x117D0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM11_MEM3_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x117F0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM12_MEM0_BLK_CFG_W [64]

MBC Memory Block Configuration Word, array offset: 0x11840, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM12_MEM0_BLK_NSE_W [16]

MBC Memory Block NonSecure Enable Word, array offset: 0x11940, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM12_MEM1_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x11980, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM12_MEM1_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x119A0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM12_MEM2_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x119A8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM12_MEM2_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x119C8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM12_MEM3_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x119D0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM12_MEM3_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x119F0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM13_MEM0_BLK_CFG_W [64]

MBC Memory Block Configuration Word, array offset: 0x11A40, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM13_MEM0_BLK_NSE_W [16]

MBC Memory Block NonSecure Enable Word, array offset: 0x11B40, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM13_MEM1_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x11B80, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM13_MEM1_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x11BA0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM13_MEM2_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x11BA8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM13_MEM2_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x11BC8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM13_MEM3_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x11BD0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM13_MEM3_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x11BF0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM14_MEM0_BLK_CFG_W [64]

MBC Memory Block Configuration Word, array offset: 0x11C40, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM14_MEM0_BLK_NSE_W [16]

MBC Memory Block NonSecure Enable Word, array offset: 0x11D40, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM14_MEM1_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x11D80, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM14_MEM1_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x11DA0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM14_MEM2_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x11DA8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM14_MEM2_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x11DC8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM14_MEM3_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x11DD0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM14_MEM3_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x11DF0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM15_MEM0_BLK_CFG_W [64]

MBC Memory Block Configuration Word, array offset: 0x11E40, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM15_MEM0_BLK_NSE_W [16]

MBC Memory Block NonSecure Enable Word, array offset: 0x11F40, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM15_MEM1_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x11F80, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM15_MEM1_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x11FA0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM15_MEM2_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x11FA8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM15_MEM2_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x11FC8, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM15_MEM3_BLK_CFG_W [8]

MBC Memory Block Configuration Word, array offset: 0x11FD0, array step: index*0x2000, index2*0x4

___IO uint32_t MBC_DOM15_MEM3_BLK_NSE_W [2]

MBC Memory Block NonSecure Enable Word, array offset: 0x11FF0, array step: index*0x2000, index2*0x4

struct _TRDC_MRC_Type

#include <fsl_trdc_core.h> TRDC MRC control register definition. MRC_DOM0_RGD_W[region][word].

Public Members

___I uint32_t MRC_GLBCFG

MRC Global Configuration Register, array offset: 0x14000, array step: 0x1000

___IO uint32_t MRC_NSE_RGN_INDIRECT

MRC NonSecure Enable Region Indirect, array offset: 0x14010, array step: 0x1000

___O uint32_t MRC_NSE_RGN_SET

MRC NonSecure Enable Region Set, array offset: 0x14014, array step: 0x1000

___O uint32_t MRC_NSE_RGN_CLR

MRC NonSecure Enable Region Clear, array offset: 0x14018, array step: 0x1000

___O uint32_t MRC_NSE_RGN_CLR_ALL

MRC NonSecure Enable Region Clear All, array offset: 0x1401C, array step: 0x1000

___IO uint32_t MRC_GLBAC [8]

MRC Global Access Control, array offset: 0x14020, array step: index*0x1000, index2*0x4

___IO uint32_t MRC_DOM0_RGD_W [16][2]

MRC Region Descriptor Word 0..MRC Region Descriptor Word 1, array offset: 0x14040, array step: index*0x1000, index2*0x8, index3*0x4

___IO uint32_t MRC_DOM0_RGD_NSE

MRC Region Descriptor NonSecure Enable, array offset: 0x140C0, array step: 0x1000

___IO uint32_t MRC_DOM1_RGD_W [16][2]

MRC Region Descriptor Word 0..MRC Region Descriptor Word 1, array offset: 0x14140, array step: index*0x1000, index2*0x8, index3*0x4

___IO uint32_t MRC_DOM1_RGD_NSE

MRC Region Descriptor NonSecure Enable, array offset: 0x141C0, array step: 0x1000

___IO uint32_t MRC_DOM2_RGD_W [16][2]

MRC Region Descriptor Word 0..MRC Region Descriptor Word 1, array offset: 0x14240, array step: index*0x1000, index2*0x8, index3*0x4

___IO uint32_t MRC_DOM2_RGD_NSE

MRC Region Descriptor NonSecure Enable, array offset: 0x142C0, array step: 0x1000

___IO uint32_t MRC_DOM3_RGD_W [16][2]

MRC Region Descriptor Word 0..MRC Region Descriptor Word 1, array offset: 0x14340, array step: index*0x1000, index2*0x8, index3*0x4

___IO uint32_t MRC_DOM3_RGD_NSE

MRC Region Descriptor NonSecure Enable, array offset: 0x143C0, array step: 0x1000

___IO uint32_t MRC_DOM4_RGD_W [16][2]

MRC Region Descriptor Word 0..MRC Region Descriptor Word 1, array offset: 0x14440, array step: index*0x1000, index2*0x8, index3*0x4

___IO uint32_t MRC_DOM4_RGD_NSE

MRC Region Descriptor NonSecure Enable, array offset: 0x144C0, array step: 0x1000

___IO uint32_t MRC_DOM5_RGD_W [16][2]

MRC Region Descriptor Word 0..MRC Region Descriptor Word 1, array offset: 0x14540, array step: index*0x1000, index2*0x8, index3*0x4

___IO uint32_t MRC_DOM5_RGD_NSE

MRC Region Descriptor NonSecure Enable, array offset: 0x145C0, array step: 0x1000

___IO uint32_t MRC_DOM6_RGD_W [16][2]

MRC Region Descriptor Word 0..MRC Region Descriptor Word 1, array offset: 0x14640, array step: index*0x1000, index2*0x8, index3*0x4

___IO uint32_t MRC_DOM6_RGD_NSE

MRC Region Descriptor NonSecure Enable, array offset: 0x146C0, array step: 0x1000

___IO uint32_t MRC_DOM7_RGD_W [16][2]

MRC Region Descriptor Word 0..MRC Region Descriptor Word 1, array offset: 0x14740, array step: index*0x1000, index2*0x8, index3*0x4

___IO uint32_t MRC_DOM7_RGD_NSE

MRC Region Descriptor NonSecure Enable, array offset: 0x147C0, array step: 0x1000

___IO uint32_t MRC_DOM8_RGD_W [16][2]

MRC Region Descriptor Word 0..MRC Region Descriptor Word 1, array offset: 0x14840, array step: index*0x1000, index2*0x8, index3*0x4

___IO uint32_t MRC_DOM8_RGD_NSE

MRC Region Descriptor NonSecure Enable, array offset: 0x148C0, array step: 0x1000

___IO uint32_t MRC_DOM9_RGD_W [16][2]

MRC Region Descriptor Word 0..MRC Region Descriptor Word 1, array offset: 0x14940, array step: index*0x1000, index2*0x8, index3*0x4

___IO uint32_t MRC_DOM9_RGD_NSE

MRC Region Descriptor NonSecure Enable, array offset: 0x149C0, array step: 0x1000

___IO uint32_t MRC_DOM10_RGD_W [16][2]

MRC Region Descriptor Word 0..MRC Region Descriptor Word 1, array offset: 0x14A40, array step: index*0x1000, index2*0x8, index3*0x4

___IO uint32_t MRC_DOM10_RGD_NSE

MRC Region Descriptor NonSecure Enable, array offset: 0x14AC0, array step: 0x1000

___IO uint32_t MRC_DOM11_RGD_W [16][2]

MRC Region Descriptor Word 0..MRC Region Descriptor Word 1, array offset: 0x14B40, array step: index*0x1000, index2*0x8, index3*0x4

___IO uint32_t MRC_DOM11_RGD_NSE

MRC Region Descriptor NonSecure Enable, array offset: 0x14BC0, array step: 0x1000

___IO uint32_t MRC_DOM12_RGD_W [16][2]

MRC Region Descriptor Word 0..MRC Region Descriptor Word 1, array offset: 0x14C40, array step: index*0x1000, index2*0x8, index3*0x4

___IO uint32_t MRC_DOM12_RGD_NSE

MRC Region Descriptor NonSecure Enable, array offset: 0x14CC0, array step: 0x1000

___IO uint32_t MRC_DOM13_RGD_W [16][2]

MRC Region Descriptor Word 0..MRC Region Descriptor Word 1, array offset: 0x14D40, array step: index*0x1000, index2*0x8, index3*0x4

___IO uint32_t MRC_DOM13_RGD_NSE

MRC Region Descriptor NonSecure Enable, array offset: 0x14DC0, array step: 0x1000

___IO uint32_t MRC_DOM14_RGD_W [16][2]

MRC Region Descriptor Word 0..MRC Region Descriptor Word 1, array offset: 0x14E40, array step: index*0x1000, index2*0x8, index3*0x4

___IO uint32_t MRC_DOM14_RGD_NSE

MRC Region Descriptor NonSecure Enable, array offset: 0x14EC0, array step: 0x1000

___IO uint32_t MRC_DOM15_RGD_W [16][2]

MRC Region Descriptor Word 0..MRC Region Descriptor Word 1, array offset: 0x14F40, array step: index*0x1000, index2*0x8, index3*0x4

___IO uint32_t MRC_DOM15_RGD_NSE

MRC Region Descriptor NonSecure Enable, array offset: 0x14FC0, array step: 0x1000

struct MBC_DERR

Public Members

___I uint32_t W0

MBC Domain Error Word0 Register, array offset: 0x400, array step: 0x10

___I uint32_t W1

MBC Domain Error Word1 Register, array offset: 0x404, array step: 0x10

___O uint32_t W3

MBC Domain Error Word3 Register, array offset: 0x40C, array step: 0x10

struct MRC_DERR

Public Members

___I uint32_t W0

MRC Domain Error Word0 Register, array offset: 0x480, array step: 0x10

___I uint32_t W1

MRC Domain Error Word1 Register, array offset: 0x484, array step: 0x10

___O uint32_t W3

MRC Domain Error Word3 Register, array offset: 0x48C, array step: 0x10

union ___unnamed79___

Public Members

struct *_TRDC_DomainAssignment_Type* MDA_DFMT0[8]

struct *_TRDC_DomainAssignment_Type* MDA_DFMT1[8]

struct MDA_DFMT0

Public Members

___IO uint32_t MDA_W_DFMT0 [8]

DAC Master Domain Assignment Register, array offset: 0x800, array step: index*0x20, index2*0x4

struct MDA_DFMT1

Public Members

___IO uint32_t MDA_W_DFMT1 [1]

DAC Master Domain Assignment Register, array offset: 0x800, array step: index*0x20, index2*0x4

2.76 TRNG: True Random Number Generator

FSL_TRNG_DRIVER_VERSION

TRNG driver version 2.0.23.

Current version: 2.0.23

Change log:

- version 2.0.23
  - Updated TRNG default values for MCXA577 devices based on silicon characterization.
- version 2.0.22
  - Added support for KW43 and MCXW70 devices.
- version 2.0.21
  - Added support for MCXC devices.
- version 2.0.20
  - Added support for MCXA devices.
- version 2.0.19
  - Added support for MCXA and MCXL.
- version 2.0.18
  - TRNG health checks now done in software on RT5xx and RT6xx.
- version 2.0.17

  - Added support for RT700.
- version 2.0.16
  - Added support for Dual oscillator mode.
- version 2.0.15
  - Changed TRNG_USER_CONFIG_DEFAULT_XXX values according to latest reccomended by design team.
- version 2.0.14
  - add support for RW610 and RW612
- version 2.0.13
  - After deepsleep it might return error, added clearing bits in *TRNG_GetRandomData()* and generating new entropy.
  - Modified reloading entropy in *TRNG_GetRandomData()*, for some data length it doesn't reloading entropy correctly.
- version 2.0.12
  - For KW34A4_SERIES, KW35A4_SERIES, KW36A4_SERIES set TRNG_USER_CONFIG_DEFAULT_OSC_DIV to kTRNG_RingOscDiv8.
- version 2.0.11
  - Add clearing pending errors in *TRNG_Init()*.
- version 2.0.10
  - Fixed doxygen issues.
- version 2.0.9
  - Fix HIS_CCM metrics issues.
- version 2.0.8
  - For K32L2A41A_SERIES set TRNG_USER_CONFIG_DEFAULT_OSC_DIV to kTRNG_RingOscDiv4.
- version 2.0.7
  - Fix MISRA 2004 issue rule 12.5.
- version 2.0.6
  - For KW35Z4_SERIES set TRNG_USER_CONFIG_DEFAULT_OSC_DIV to kTRNG_RingOscDiv8.
- version 2.0.5
  - Add possibility to define default TRNG configuration by device specific preprocessor macros for FRQMIN, FRQMAX and OSCDIV.
- version 2.0.4
  - Fix MISRA-2012 issues.
- Version 2.0.3
  - update TRNG_Init to restart entropy generation
- Version 2.0.2
  - fix MISRA issues
- Version 2.0.1
  - add support for KL8x and KL28Z

- update default OSCDIV for K81 to divide by 2

enum _trng_sample_mode

TRNG sample mode. Used by trng_config_t.

Values:

enumerator kTRNG_SampleModeVonNeumann

Use von Neumann data in both Entropy shifter and Statistical Checker.

enumerator kTRNG_SampleModeRaw

Use raw data into both Entropy shifter and Statistical Checker.

enumerator kTRNG_SampleModeVonNeumannRaw

Use von Neumann data in Entropy shifter. Use raw data into Statistical Checker.

enum _trng_clock_mode

TRNG clock mode. Used by trng_config_t.

Values:

enumerator kTRNG_ClockModeRingOscillator

Ring oscillator is used to operate the TRNG (default).

enumerator kTRNG_ClockModeSystem

System clock is used to operate the TRNG. This is for test use only, and indeterminate results may occur.

enum _trng_ring_osc_div

TRNG ring oscillator divide. Used by trng_config_t.

Values:

enumerator kTRNG_RingOscDiv0

Ring oscillator with no divide

enumerator kTRNG_RingOscDiv2

Ring oscillator divided-by-2.

enumerator kTRNG_RingOscDiv4

Ring oscillator divided-by-4.

enumerator kTRNG_RingOscDiv8

Ring oscillator divided-by-8.

enum trng_oscillator_mode_t

TRNG oscillator mode . Used by trng_config_t.

Values:

enumerator kTRNG_SingleOscillatorModeOsc1

Single oscillator mode, using OSC1 (default)

enumerator kTRNG_DualOscillatorMode

Dual oscillator mode

enumerator kTRNG_SingleOscillatorModeOsc2

Single oscillator mode, using OSC2

typedef enum *_trng_sample_mode* trng_sample_mode_t

TRNG sample mode. Used by trng_config_t.

typedef enum *_trng_clock_mode* trng_clock_mode_t

TRNG clock mode. Used by trng_config_t.

typedef enum *_trng_ring_osc_div* trng_ring_osc_div_t

TRNG ring oscillator divide. Used by trng_config_t.

typedef enum *trng_oscillator_mode_t* trng_oscillator_mode_t

TRNG oscillator mode . Used by trng_config_t.

typedef struct *_trng_statistical_check_limit* trng_statistical_check_limit_t

Data structure for definition of statistical check limits. Used by trng_config_t.

typedef struct *_trng_user_config* trng_config_t

Data structure for the TRNG initialization.

This structure initializes the TRNG by calling the *TRNG_Init()* function. It contains all TRNG configurations.

status_t TRNG_GetDefaultConfig(*trng_config_t* *userConfig)

Initializes the user configuration structure to default values.

This function initializes the configuration structure to default values. The default values are platform dependent.

Parameters

- userConfig – User configuration structure.

Returns

If successful, returns the kStatus_TRNG_Success. Otherwise, it returns an error.

status_t TRNG_Init(TRNG_Type *base, const *trng_config_t* *userConfig)

Initializes the TRNG.

This function initializes the TRNG. When called, the TRNG entropy generation starts immediately.

Parameters

- base – TRNG base address
- userConfig – Pointer to the initialization configuration structure.

Returns

If successful, returns the kStatus_TRNG_Success. Otherwise, it returns an error.

void TRNG_Deinit(TRNG_Type *base)

Shuts down the TRNG.

This function shuts down the TRNG.

Parameters

- base – TRNG base address.

status_t TRNG_GetRandomData(TRNG_Type *base, void *data, size_t dataSize)

Gets random data.

This function gets random data from the TRNG.

Parameters

- base – TRNG base address.
- data – Pointer address used to store random data.
- dataSize – Size of the buffer pointed by the data parameter.

Returns

random data

struct _trng_statistical_check_limit

#include <fsl_trng.h> Data structure for definition of statistical check limits. Used by trng_config_t.

Public Members

uint32_t maximum

Maximum limit.

int32_t minimum

Minimum limit.

struct _trng_user_config

#include <fsl_trng.h> Data structure for the TRNG initialization.

This structure initializes the TRNG by calling the *TRNG_Init()* function. It contains all TRNG configurations.

Public Members

bool lock

Disable programmability of TRNG registers.

trng_clock_mode_t clockMode

Clock mode used to operate TRNG.

trng_ring_osc_div_t ringOscDiv

Ring oscillator divide used by TRNG.

trng_sample_mode_t sampleMode

Sample mode of the TRNG ring oscillator.

trng_oscillator_mode_t oscillatorMode

TRNG oscillator mode .

trng_ring_osc_div_t ringOsc2Div

Divider used for Ring oscillator 2.

uint16_t entropyDelay

Entropy Delay. Defines the length (in system clocks) of each Entropy sample taken.

uint16_t sampleSize

Sample Size. Defines the total number of Entropy samples that will be taken during Entropy generation.

uint16_t sparseBitLimit

Sparse Bit Limit which defines the maximum number of consecutive samples that may be discarded before an error is generated. This limit is used only for during von Neumann sampling (enabled by TRNG_HAL_SetSampleMode()). Samples are discarded if two consecutive raw samples are both 0 or both 1. If this discarding occurs for a long period of time, it indicates that there is insufficient Entropy.

uint8_t retryCount

Retry count. It defines the number of times a statistical check may fails during the TRNG Entropy Generation before generating an error.

uint8_t longRunMaxLimit

Largest allowable number of consecutive samples of all 1, or all 0, that is allowed during the Entropy generation.

trng_statistical_check_limit_t monobitLimit

Maximum and minimum limits for statistical check of number of ones/zero detected during entropy generation.

trng_statistical_check_limit_t runBit1Limit

Maximum and minimum limits for statistical check of number of runs of length 1 detected during entropy generation.

trng_statistical_check_limit_t runBit2Limit

Maximum and minimum limits for statistical check of number of runs of length 2 detected during entropy generation.

trng_statistical_check_limit_t runBit3Limit

Maximum and minimum limits for statistical check of number of runs of length 3 detected during entropy generation.

trng_statistical_check_limit_t runBit4Limit

Maximum and minimum limits for statistical check of number of runs of length 4 detected during entropy generation.

trng_statistical_check_limit_t runBit5Limit

Maximum and minimum limits for statistical check of number of runs of length 5 detected during entropy generation.

trng_statistical_check_limit_t runBit6PlusLimit

Maximum and minimum limits for statistical check of number of runs of length 6 or more detected during entropy generation.

trng_statistical_check_limit_t pokerLimit

Maximum and minimum limits for statistical check of “Poker Test”.

trng_statistical_check_limit_t frequencyCountLimit

Maximum and minimum limits for statistical check of entropy sample frequency count.

2.77 UTICK: MictoTick Timer Driver

void UTICK_Init(UTICK_Type *base)

Initializes an UTICK by turning its bus clock on.

void UTICK_Deinit(UTICK_Type *base)

Deinitializes a UTICK instance.

This function shuts down Utick bus clock

Parameters

- base – UTICK peripheral base address.

uint32_t UTICK_GetStatusFlags(UTICK_Type *base)

Get Status Flags.

This returns the status flag

Parameters

- base – UTICK peripheral base address.

Returns

status register value

void UTICK_ClearStatusFlags(UTICK_Type *base)

Clear Status Interrupt Flags.

This clears intr status flag

Parameters

- base – UTICK peripheral base address.

Returns

none

void UTICK_SetTick(UTICK_Type *base, *utick_mode_t* mode, uint32_t count, *utick_callback_t* cb)

Starts UTICK.

This function starts a repeat/onetime countdown with an optional callback

Parameters

- base – UTICK peripheral base address.
- mode – UTICK timer mode (ie kUTICK_onetime or kUTICK_repeat)
- count – UTICK timer mode (ie kUTICK_onetime or kUTICK_repeat)
- cb – UTICK callback (can be left as NULL if none, otherwise should be a void func(void))

Returns
none

void UTICK_HandleIRQ(UTICK_Type *base, *utick_callback_t* cb)

UTICK Interrupt Service Handler.

This function handles the interrupt and refers to the callback array in the driver to callback user (as per request in *UTICK_SetTick()*). if no user callback is scheduled, the interrupt will simply be cleared.

Parameters

- base – UTICK peripheral base address.
- cb – callback scheduled for this instance of UTICK

Returns
none

FSL_UTICK_DRIVER_VERSION

UTICK driver version 2.0.6.

enum _utick_mode

UTICK timer operational mode.

Values:

enumerator kUTICK_Onetime

Trigger once

enumerator kUTICK_Repeat

Trigger repeatedly

typedef enum *_utick_mode* utick_mode_t

UTICK timer operational mode.

typedef void (*utick_callback_t)(void)

UTICK callback function.

2.78 WAKETIMER: WAKETIMER Driver

void WAKETIMER_Init(WAKETIMER_Type *base, const *waketimer_config_t* *config)

Initializes an WAKETIMER.

This function initializes the WAKETIMER.

Parameters

- base – WAKETIMER peripheral base address.
- config – Pointer to the user configuration structure.

void WAKETIMER_Deinit(WAKETIMER_Type *base)

Deinitializes a WAKETIMER instance.

This function deinitialize the WAKETIMER.

Parameters

- base – WAKETIMER peripheral base address.

void WAKETIMER_GetDefaultConfig(*waketimer_config_t* *config)

Fills in the WAKETIMER configuration structure with the default settings.

The default values are:

```
config->enableInterrupt = true;
config->enableOSCDivide = true;
config->callback        = NULL;
```

Parameters

- config – Pointer to the user configuration structure.

void WAKETIMER_EnableInterrupts(WAKETIMER_Type *base, uint32_t mask)

Enables the selected WAKETIMER interrupts.

Parameters

- base – WAKETIMER peripheral base address
- mask – Mask value for interrupt events. See to *_waketimer_interrupt_enable*

void WAKETIMER_DisableInterrupts(WAKETIMER_Type *base, uint32_t mask)

Enables the selected WAKETIMER interrupts.

Parameters

- base – WAKETIMER peripheral base address
- mask – Mask value for interrupt events. See to *_waketimer_interrupt_enable*

void WAKETIMER_ClearStatusFlags(WAKETIMER_Type *base, uint32_t mask)

Clear Status Interrupt Flag.

This clears intrrupt status flag. Currently, only match interrupt flag can be cleared.

Parameters

- base – WAKETIMER peripheral base address.
- mask – Mask value for flags to be cleared. See to *_waketimer_status_flags*.

Returns

none

void WAKETIMER_SetCallback(WAKETIMER_Type *base, *waketimer_callback_t* callback)

Receive noticification when waketime countdown.

If the interrupt for the waketime countdown is enabled, then a callback can be registered which will be invoked when the event is triggered

Parameters

- base – WAKETIMER peripheral base address
- callback – Function to invoke when the event is triggered

static inline void WAKETIMER_HaltTimer(WAKETIMER_Type *base)

Halt and clear timer counter.

This halt and clear timer counter.

Parameters

- base – WAKETIMER peripheral base address.

Returns

none

static inline void WAKETIMER_StartTimer(WAKETIMER_Type *base, uint32_t value)

Set timer counter.

This set the timer counter and start the timer countdown.

Parameters

- base – WAKETIMER peripheral base address.
- value – countdown value.

Returns

none

uint32_t WAKETIMER_GetCurrentTimerValue(WAKETIMER_Type *base)

Get current timer count value from WAKETIMER.

This function will get a decimal timer count value. The RAW value of timer count is gray code format, will be translated to decimal data internally.

Parameters

- base – WAKETIMER peripheral base address.

Returns

Value of WAKETIMER which will be formated to decimal value.

FSL_WAKETIMER_DRIVER_VERSION

WAKETIMER driver version.

enum _waketimer_status_flags

WAKETIMER status flags.

Values:

enumerator kWAKETIMER_WakeFlag

Wake Timer Status Flag, sets wake timer has timed out.

enum _waketimer_interrupt_enable

Define interrupt switchers of the module.

Values:

enumerator kWAKETIMER_WakeInterruptEnable

Generate interrupt requests when WAKE_FLAG is asserted.

typedef void (*waketimer_callback_t)(void)

waketimer callback function.

typedef struct *_waketimer_config* waketimer__config__t

WAKETIMER configuration structure.

This structure holds the configuration settings for the WAKETIMER peripheral. To initialize this structure to reasonable defaults, call the *WAKETIMER_GetDefaultConfig()* function and pass a pointer to the configuration structure instance.

The configuration structure can be made constant so as to reside in flash.

struct __waketimer__config

#include <fsl_waketimer.h> WAKETIMER configuration structure.

This structure holds the configuration settings for the WAKETIMER peripheral. To initialize this structure to reasonable defaults, call the *WAKETIMER_GetDefaultConfig()* function and pass a pointer to the configuration structure instance.

The configuration structure can be made constant so as to reside in flash.

Public Members

bool enableOSCDivide

true: Enable OSC Divide. false: Disable OSC Divide.

bool enableInterrupt

true: Enable interrupt. false: Disable interrupt.

waketimer_callback_t callback

timer countdown callback.

2.79 WUU: Wakeup Unit driver

void WUU__SetExternalWakeUpPinsConfig(WUU_Type *base, uint8_t pinIndex, const *wuu_external_wakeup_pin_config_t* *config)

Enables and Configs External WakeUp Pins.

This function enables/disables the external pin as wakeup input. What's more this function configs pins options, including edge detection wakeup event and operate mode.

Parameters

- base – MUU peripheral base address.
- pinIndex – The index of the external input pin. See Reference Manual for the details.
- config – Pointer to wuu_external_wakeup_pin_config_t structure.

void WUU__ClearExternalWakeupPinsConfig(WUU_Type *base, uint8_t pinIndex)

Disable and clear external wakeup pin settings.

Parameters

- base – MUU peripheral base address.
- pinIndex – The index of the external input pin.

static inline uint32_t WUU_GetExternalWakeUpPinsFlag(WUU_Type *base)

Gets External Wakeup pin flags.

This function return the external wakeup pin flags.

Parameters

- base – WUU peripheral base address.

Returns

Wakeup flags for all external wakeup pins.

static inline void WUU_ClearExternalWakeUpPinsFlag(WUU_Type *base, uint32_t mask)

Clears External WakeUp Pin flags.

This function clears external wakeup pins flags based on the mask.

Parameters

- base – WUU peripheral base address.
- mask – The mask of Wakeup pin index to be cleared.

void WUU_SetInternalWakeUpModulesConfig(WUU_Type *base, uint8_t moduleIndex, *wuu_internal_wakeup_module_event_t* event)

Config Internal modules' event as the wake up soures.

This function configs the internal modules event as the wake up sources.

Parameters

- base – WUU peripheral base address.
- moduleIndex – The selected internal module. See the Reference Manual for the details.
- event – Select interrupt or DMA/Trigger of the internal module as the wake up source.

void WUU_ClearInternalWakeUpModulesConfig(WUU_Type *base, uint8_t moduleIndex, *wuu_internal_wakeup_module_event_t* event)

Disable an on-chip internal modules' event as the wakeup sources.

Parameters

- base – WUU peripheral base address.
- moduleIndex – The selected internal module. See the Reference Manual for the details.
- event – The event(interrupt or DMA/trigger) of the internal module to disable.

static inline uint32_t WUU_GetModuleInterruptFlag(WUU_Type *base)

Get wakeup flags for internal wakeup modules.

Parameters

- base – WUU peripheral base address.

Returns

Wakeup flags for all internal wakeup modules.

static inline bool WUU_GetInternalWakeupModuleFlag(WUU_Type *base, uint32_t moduleIndex)

Gets the internal module wakeup source flag.

This function checks the flag to detect whether the system is woken up by specific on-chip module interrupt.

Parameters

- base – WWU peripheral base address.
- moduleIndex – A module index, which starts from 0.

Returns
True if the specific pin is a wake up source.

void WUU_SetPinFilterConfig(WUU_Type *base, uint8_t filterIndex, const *wuu_pin_filter_config_t* *config)

Configs and Enables Pin filters.

This function configs Pin filter, including pin select, filer operate mode filer wakeup event and filter edge detection.

Parameters

- base – WUU peripheral base address.
- filterIndex – The index of the pin filer.
- config – Pointer to wuu_pin_filter_config_t structure.

bool WUU_GetPinFilterFlag(WUU_Type *base, uint8_t filterIndex)

Gets the pin filter configuration.

This function gets the pin filter flag.

Parameters

- base – WUU peripheral base address.
- filterIndex – A pin filter index, which starts from 1.

Returns
True if the flag is a source of the existing low-leakage power mode.

void WUU_ClearPinFilterFlag(WUU_Type *base, uint8_t filterIndex)

Clears the pin filter configuration.

This function clears the pin filter flag.

Parameters

- base – WUU peripheral base address.
- filterIndex – A pin filter index to clear the flag, starting from 1.

bool WUU_GetExternalWakeupPinFlag(WUU_Type *base, uint32_t pinIndex)

brief Gets the external wakeup source flag.

This function checks the external pin flag to detect whether the MCU is woken up by the specific pin.

param base WUU peripheral base address. param pinIndex A pin index, which starts from 0. return True if the specific pin is a wakeup source.

void WUU_ClearExternalWakeupPinFlag(WUU_Type *base, uint32_t pinIndex)

brief Clears the external wakeup source flag.

This function clears the external wakeup source flag for a specific pin.

param base WUU peripheral base address. param pinIndex A pin index, which starts from 0.

FSL_WUU_DRIVER_VERSION

Defines WUU driver version 2.4.2.

enum _wuu_external_pin_edge_detection

External WakeUp pin edge detection enumeration.

Values:

enumerator kWUU_ExternalPinDisable

External input Pin disabled as wake up input.

enumerator kWUU_ExternalPinRisingEdge

External input Pin enabled with the rising edge detection.

enumerator kWUU_ExternalPinFallingEdge

External input Pin enabled with the falling edge detection.

enumerator kWUU_ExternalPinAnyEdge

External input Pin enabled with any change detection.

enum _wuu_external_wakeup_pin_event

External input wake up pin event enumeration.

Values:

enumerator kWUU_ExternalPinInterrupt

External input Pin configured as interrupt.

enumerator kWUU_ExternalPinDMARequest

External input Pin configured as DMA request.

enumerator kWUU_ExternalPinTriggerEvent

External input Pin configured as Trigger event.

enum _wuu_external_wakeup_pin_mode

External input wake up pin mode enumeration.

Values:

enumerator kWUU_ExternalPinActiveDSPD

External input Pin is active only during Deep Sleep/Power Down Mode. NOTE: This enumerations has been deprecated, please switch to kWUU_ExternalPinActiveLowLeakage.

enumerator kWUU_ExternalPinActiveLowLeakageMode

External input Pin is active only during low-leakage power modes.

enumerator kWUU_ExternalPinActiveAlways

External input Pin is active during all power modes.

enum _wuu_internal_wakeup_module_event

Internal module wake up event enumeration.

Values:

enumerator kWUU_InternalModuleInterrupt
Internal modules' interrupt as a wakeup source.

enumerator kWUU_InternalModuleDMATrigger
Internal modules' DMA/Trigger as a wakeup source.

enum _wuu_filter_edge
Pin filter edge enumeration.

Values:

enumerator kWUU_FilterDisabled
Filter disabled.

enumerator kWUU_FilterPosedgeEnable
Filter posedge detect enabled.

enumerator kWUU_FilterNegedgeEnable
Filter negedge detect enabled.

enumerator kWUU_FilterAnyEdge
Filter any edge detect enabled.

enum _wuu_filter_event
Pin Filter event enumeration.

Values:

enumerator kWUU_FilterInterrupt
Filter output configured as interrupt.

enumerator kWUU_FilterDMARequest
Filter output configured as DMA request.

enumerator kWUU_FilterTriggerEvent
Filter output configured as Trigger event.

enum _wuu_filter_mode
Pin filter mode enumeration.

Values:

enumerator kWUU_FilterActiveDSPD
External input pin filter is active only during Deep Sleep/Power Down Mode. NOTE: This enumerations has been deprecated, please switch to kWUU_FilterActiveLowLeakage.

enumerator kWUU_FilterActiveLowLeakageMode
External input pin filter is active only during low-leakage power modes.

enumerator kWUU_FilterActiveAlways
External input Pin filter is active during all power modes.

typedef enum *_wuu_external_pin_edge_detection* wuu_external_pin_edge_detection_t
External WakeUp pin edge detection enumeration.

typedef enum *_wuu_external_wakeup_pin_event* wuu_external_wakeup_pin_event_t
External input wake up pin event enumeration.

typedef enum *_wuu_external_wakeup_pin_mode* wuu_external_wakeup_pin_mode_t
External input wake up pin mode enumeration.

typedef enum *_wuu_internal_wakeup_module_event* wuu_internal_wakeup_module_event_t
Internal module wake up event enumeration.

typedef enum *_wuu_filter_edge* wuu_filter_edge_t
Pin filter edge enumeration.

typedef enum *_wuu_filter_event* wuu_filter_event_t
Pin Filter event enumeration.

typedef enum *_wuu_filter_mode* wuu_filter_mode_t
Pin filter mode enumeration.

typedef struct *_wuu_external_wakeup_pin_config* wuu_external_wakeup_pin_config_t
External WakeUp pin configuration.

typedef struct *_wuu_pin_filter_config* wuu_pin_filter_config_t
Pin Filter configuration.

struct __wuu_external_wakeup_pin_config
#include <fsl_wuu.h> External WakeUp pin configuration.

Public Members

wuu_external_pin_edge_detection_t edge
External Input pin edge detection.

wuu_external_wakeup_pin_event_t event
External Input wakeup Pin event

wuu_external_wakeup_pin_mode_t mode
External Input wakeup Pin operate mode.

struct __wuu_pin_filter_config
#include <fsl_wuu.h> Pin Filter configuration.

Public Members

uint32_t pinIndex

The index of wakeup pin to be muxxed into filter.

wuu_filter_edge_t edge

The edge of the pin digital filter.

wuu_filter_event_t event

The event of the filter output.

wuu_filter_mode_t mode

The mode of the filter operate.

2.80 WWDT: Windowed Watchdog Timer Driver

void WWDT_GetDefaultConfig(*wwdt_config_t* *config)

Initializes WWDT configure structure.

This function initializes the WWDT configure structure to default value. The default value are:

```
config->enableWwdt = true;
config->enableWatchdogReset = false;
config->enableWatchdogProtect = false;
config->enableLockOscillator = false;
config->windowValue = 0xFFFFFFU;
config->timeoutValue = 0xFFFFFFU;
config->warningValue = 0;
```

See also:

wwdt_config_t

Parameters

- config – Pointer to WWDT config structure.

void WWDT_Init(WWDT_Type *base, const *wwdt_config_t* *config)

Initializes the WWDT.

This function initializes the WWDT. When called, the WWDT runs according to the configuration.

Example:

```
wwdt_config_t config;
WWDT_GetDefaultConfig(&config);
config.timeoutValue = 0x7ffU;
WWDT_Init(wwdt_base,&config);
```

Parameters

- base – WWDT peripheral base address
- config – The configuration of WWDT

void WWDT_Deinit(WWDT_Type *base)

Shuts down the WWDT.

This function shuts down the WWDT.

Parameters

- base – WWDT peripheral base address

static inline void WWDT_Enable(WWDT_Type *base)

Enables the WWDT module.

This function write value into WWDT_MOD register to enable the WWDT, it is a write-once bit; once this bit is set to one and a watchdog feed is performed, the watchdog timer will run permanently.

Parameters

- base – WWDT peripheral base address

static inline void WWDT_Disable(WWDT_Type *base)

Disables the WWDT module.

Deprecated:

Do not use this function. It will be deleted in next release version, for once the bit field of WDEN written with a 1, it can not be re-written with a 0.

This function write value into WWDT_MOD register to disable the WWDT.

Parameters

- base – WWDT peripheral base address

static inline uint32_t WWDT_GetStatusFlags(WWDT_Type *base)

Gets all WWDT status flags.

This function gets all status flags.

Example for getting Timeout Flag:

```
uint32_t status;
status = WWDT_GetStatusFlags(wwdt_base) & kWWDT_TimeoutFlag;
```

Parameters

- base – WWDT peripheral base address

Returns

The status flags. This is the logical OR of members of the enumeration *_wwdt_status_flags_t*

void WWDT_ClearStatusFlags(WWDT_Type *base, uint32_t mask)

Clear WWDT flag.

This function clears WWDT status flag.

Example for clearing warning flag:

```
WWDT_ClearStatusFlags(wwdt_base, kWWDT_WarningFlag);
```

Parameters

- base – WWDT peripheral base address
- mask – The status flags to clear. This is a logical OR of members of the enumeration *_wwdt_status_flags_t*

static inline void WWDT_SetWarningValue(WWDT_Type *base, uint32_t warningValue)

Set the WWDT warning value.

The WDWARNINT register determines the watchdog timer counter value that will generate a watchdog interrupt. When the watchdog timer counter is no longer greater than the value defined by WARNINT, an interrupt will be generated after the subsequent WDCLK.

Parameters

- base – WWDT peripheral base address
- warningValue – WWDT warning value.

static inline void WWDT_SetTimeoutValue(WWDT_Type *base, uint32_t timeoutCount)

Set the WWDT timeout value.

This function sets the timeout value. Every time a feed sequence occurs the value in the TC register is loaded into the Watchdog timer. Writing a value below 0xFF will cause 0xFF to be loaded into the TC register. Thus the minimum time-out interval is TWDCLK*256*4. If enableWatchdogProtect flag is true in wwdt_config_t config structure, any attempt to change the timeout value before the watchdog counter is below the warning and window values will cause a watchdog reset and set the WDTOF flag.

Parameters

- base – WWDT peripheral base address
- timeoutCount – WWDT timeout value, count of WWDT clock tick.

static inline void WWDT_SetWindowValue(WWDT_Type *base, uint32_t windowValue)

Sets the WWDT window value.

The WINDOW register determines the highest TV value allowed when a watchdog feed is performed. If a feed sequence occurs when timer value is greater than the value in WINDOW, a watchdog event will occur. To disable windowing, set windowValue to 0xFFFFFF (maximum possible timer value) so windowing is not in effect.

Parameters

- base – WWDT peripheral base address
- windowValue – WWDT window value.

void WWDT_Refresh(WWDT_Type *base)

Refreshes the WWDT timer.

This function feeds the WWDT. This function should be called before WWDT timer is in timeout. Otherwise, a reset is asserted.

Parameters

- base – WWDT peripheral base address

FSL_WWDT_DRIVER_VERSION

Defines WWDT driver version.

WWDT_FIRST_WORD_OF_REFRESH

First word of refresh sequence

WWDT_SECOND_WORD_OF_REFRESH

Second word of refresh sequence

enum _wwdt_status_flags_t

WWDT status flags.

This structure contains the WWDT status flags for use in the WWDT functions.

Values:

enumerator kWWDT_TimeoutFlag

Time-out flag, set when the timer times out

enumerator kWWDT_WarningFlag

Warning interrupt flag, set when timer is below the value WDWARNINT

typedef struct *_wwdt_config* wwdt_config_t

Describes WWDT configuration structure.

struct _wwdt_config

#include <fsl_wwdt.h> Describes WWDT configuration structure.

Public Members

bool enableWwdt

Enables or disables WWDT

bool enableWatchdogReset

true: Watchdog timeout will cause a chip reset false: Watchdog timeout will not cause a chip reset

bool enableWatchdogProtect

true: Enable watchdog protect i.e timeout value can only be changed after counter is below warning & window values false: Disable watchdog protect; timeout value can be changed at any time

uint32_t windowValue

Window value, set this to 0xFFFFFF if windowing is not in effect

uint32_t timeoutValue

Timeout value

uint32_t warningValue

Watchdog time counter value that will generate a warning interrupt. Set this to 0 for no warning

uint32_t clockFreq_Hz

Watchdog clock source frequency.

Chapter 3

Middleware

3.1 Boot

3.1.1 MCUboot in MCUXpresso SDK

Overview

This repository is a fork of MCUboot for MCUXpresso SDK delivery and it contains the components officially provided in NXP MCUXpresso SDK. This repository is part of the MCUXpresso SDK overall delivery which is composed of several sub-repositories/projects. Navigate to the top/parent repository (mcuxsdk-manifests) for the complete delivery of MCUXpresso SDK. This is MCUboot version 2.4.0

MCUboot in MCUXpresso SDK is a fork of the original project that aims to integrate HW features that haven't yet been covered by the upstream code. Currently these are:

- flash remapping techniques for zero-overhead image swapping
- support for encrypted XIP
- use of NXP's SB3 file

Documentation

- Overall details of MCUXpresso SDK can be reviewed here: MCUXpresso SDK Online Documentation
- MCUXpresso SDK examples based on MCUboot are described here: MCUXpresso SDK OTA Examples
- Visit MCUboot - Documentation to review details on the original contents in this sub-repo

Setup

Instructions on how to install the MCUXpresso SDK provided from GitHub via west manifest Getting Started with SDK - Detailed Installation Instructions

Contribution

Contributions are not currently accepted. If the intended contribution is not related to NXP specific code, consider contributing directly to the upstream MCUboot project. Once this MCUboot

fork is synchronized with the upstream project, such contributions will end up here as well. If the intended contribution is a bugfix or improvement for NXP porting layer or for code added or modified by NXP, please open an issue or contact NXP support.

3.2 File System

3.2.1 FatFs

MCUXpresso SDK : mcuxsdk-middleware-fatfs

Overview This repository is for FatFs middleware delivery and it contains the components officially provided in NXP MCUXpresso SDK. This repository is part of the MCUXpresso SDK overall delivery which is composed of several sub-repositories/projects. Navigate to the top/parent repository (mcuxsdk-manifests) for the complete delivery of MCUXpresso SDK.

Documentation Overall details can be reviewed here: MCUXpresso SDK Online Documentation

Visit FatFs - Documentation to review details on the contents in this sub-repo.

Setup Instructions on how to install the MCUXpresso SDK provided from GitHub via west manifest Getting Started with SDK - Detailed Installation Instructions

Contribution Contributions are not currently accepted. Guidelines to contribute will be posted in the future.

Repo Specific Content This is MCUXpresso SDK fork of FatFs (FAT file system created by ChaN). Official documentation is available at http://elm-chan.org/fsw/ff/

MCUXpresso version is extending original content by following hardware specific porting layers:

- mmc_disk
- nand_disk
- ram_disk
- sd_disk
- sdspi_disk
- usb_disk

Changelog FatFs

All notable changes to this project will be documented in this file.

The format is based on Keep a Changelog

[R0.16_rev0]

- Upgraded to version 0.16
- Applied patch https://elm-chan.org/fsw/ff/patch/ff16p1.diff
- Applied patch https://elm-chan.org/fsw/ff/patch/ffunicode.zip
- Make lb and hb variables conditional. Fix 'unused variable' issue:
  - ffunicode.c:10622:28: error: unused variable 'lb'
  - ffunicode.c:10622:7: error: unused variable 'hb'

[R0.15_rev0]

- Upgraded to version 0.15
- Applied patches from http://elm-chan.org/fsw/ff/patches.html

[R0.14b_rev1]

- Applied patches from http://elm-chan.org/fsw/ff/patches.html

[R0.14b_rev0]

- Upgraded to version 0.14b

[R0.14a_rev0]

- Upgraded to version 0.14a
- Applied patch ff14a_p1.diff and ff14a_p2.diff

[R0.14_rev0]

- Upgraded to version 0.14
- Applied patch ff14_p1.diff and ff14_p2.diff

[R0.13c_rev0]

- Upgraded to version 0.13c
- Applied patches ff_13c_p1.diff,ff_13c_p2.diff, ff_13c_p3.diff and ff_13c_p4.diff.

[R0.13b_rev0]

- Upgraded to version 0.13b

[R0.13a_rev0]

- Upgraded to version 0.13a. Added patch ff_13a_p1.diff.

[R0.12c_rev1]

- Add NAND disk support.

[R0.12c_rev0]

- Upgraded to version 0.12c and applied patches ff_12c_p1.diff and ff_12c_p2.diff.

[R0.12b_rev0]

- Upgraded to version 0.12b.

[R0.11a]

- Added glue functions for low-level drivers (SDHC, SDSPI, RAM, MMC). Modified diskio.c.
- Added RTOS wrappers to make FatFs thread safe. Modified syscall.c.
- Renamed ffconf.h to ffconf_template.h. Each application should contain its own ffconf.h.
- Included ffconf.h into diskio.c to enable the selection of physical disk from ffconf.h by macro definition.
- Conditional compilation of physical disk interfaces in diskio.c.

3.3 Motor Control

3.3.1 FreeMASTER

Communication Driver User Guide

Introduction

What is FreeMASTER? FreeMASTER is a PC-based application developed by NXP for NXP customers. It is a versatile tool usable as a real-time monitor, visualization tool, and a graphical control panel of embedded applications based on the NXP processing units.

This document describes the embedded-side software driver which implements an interface between the application and the host PC. The interface covers the following communication:

- **Serial** UART communication either over plain RS232 interface or more typically over a USB-to-Serial either external or built in a debugger probe.
- **USB** direct connection to target microcontroller
- **CAN bus**
- **TCP/IP network** wired or WiFi
- **Segger J-Link RTT**
- **JTAG** debug port communication
- ...and all of the above also using a **Zephyr** generic drivers.

The driver also supports so-called "packet-driven BDM" interface which enables a protocol-based communication over a debugging port. The BDM stands for Background Debugging Module and its physical implementation is different on each platform. Some platforms leverage a semi-standard JTAG interface, other platforms provide a custom implementation called BDM. Regardless of the name, this debugging interface enables non-intrusive access to the memory space while the target CPU is running. For basic memory read and write operations, there is no communication driver required on the target when communicating with the host PC. Use this driver to get more advanced FreeMASTER protocol features over the BDM interface. The driver must be configured for the packet-driven BDM mode, in which the host PC uses the debugging interface

to write serial command frames directly to the target memory buffer. The same method is then used to read response frames from that memory buffer.

Similar to “packet-driven BDM”, the FreeMASTER also supports a communication over [J-Link RTT]((https://www.segger.com/products/debug-probes/j-link/technology/about-real-time-transfer/) interface defined by SEGGER Microcontroller GmbH for ARM CortexM-based microcontrollers. This method also uses JTAG physical interface and enables high-speed real time communication to run over the same channel as used for application debugging.

Driver version 3 This document describes version 3 of the FreeMASTER Communication Driver. This version features the implementation of the new Serial Protocol, which significantly extends the features and security of its predecessor. The new protocol internal number is v4 and its specification is available in the documentation accompanying the driver code.

Driver V3 is deployed to modern 32-bit MCU platforms first, so the portfolio of supported platforms is smaller than for the previous V2 versions. It is recommended to keep using the V2 driver for legacy platforms, such as S08, S12, ColdFire, or Power Architecture. Reach out to FreeMASTER community or to the local NXP representative with requests for more information or to port the V3 driver to legacy MCU devices.

Thanks to a layered approach, the new driver simplifies the porting of the driver to new UART, CAN or networking communication interfaces significantly. Users are encouraged to port the driver to more NXP MCU platforms and contribute the code back to NXP for integration into future releases. Existing code and low-level driver layers may be used as an example when porting to new targets.

Note: Using the FreeMASTER tool and FreeMASTER Communication Driver is only allowed in systems based on NXP microcontroller or microprocessor unit. Use with non-NXP MCU platforms is **not permitted** by the license terms.

Target platforms The driver implementation uses the following abstraction mechanisms which simplify driver porting and supporting new communication modules:

- **General CPU Platform** (see source code in the src/platforms directory). The code in this layer is only specific to native data type sizes and CPU architectures (for example; alignment-aware memory copy routines). This driver version brings two generic implementations of 32-bit platforms supporting both little-endian and big-endian architectures. There are also implementations customized for the 56F800E family of digital signal controllers and S12Z MCUs. **Zephyr** is treated as a specific CPU platform as it brings unified user configuration (Kconfig) and generic hardware device drivers. With Zephyr, the transport layer and low-level communication layers described below are configured automatically using Kconfig and Device Tree technologies.
- **Transport Communication Layer** - The Serial, CAN, Networking, PD-BDM, and other methods of transport logic are implemented as a driver layer called FMSTR_TRANSPORT with a uniform API. A support of the Network transport also extends single-client modes of operation which are native for Serial, USB and CAN by a concept of multiple client sessions.
- **Low-level Communication Driver** - Each type of transport further defines a low-level API used to access the physical communication module. For example, the Serial transport defines a character-oriented API implemented by different serial communication modules like UART, LPUART, USART, and also USB-CDC. Similarly, the CAN transport defines a message-oriented API implemented by the FlexCAN or MCAN modules. Moreover, there are multiple different implementations for the same kind of communication peripherals. The difference between the implementation is in the way the low-level hardware registers are accessed. The *mcuxsdk* folder contains implementations which use MCUXpresso SDK drivers. These drivers should be used in applications based on the NXP MCUXpresso SDK. The “ampsdk” drivers target automotive-specific MCUs and their respective SDKs. The “dreg” implementations use a plain C-language access to hardware register addresses

which makes it a universal and the most portable solution. In this case, users are encouraged to add more drivers for other communication modules or other respective SDKs and contribute the code back to NXP for integration.

The low-level drivers defined for the Networking transport enable datagram-oriented UDP and stream TCP communication. This implementation is demonstrated using the lwIP software stack but shall be portable to other TCP/IP stacks. It may sound surprisingly, but also the Segger J-Link RTT communication driver is linked to the Networking transport (RTT is stream oriented communication handled similarly to TCP).

Replacing existing drivers For all supported platforms, the driver described in this document replaces the V2 implementation and also older driver implementations that were available separately for individual platforms (PC Master SCI drivers).

Clocks, pins, and peripheral initialization The FreeMASTER communication driver is only responsible for runtime processing of the communication and must be integrated with an user application code to function properly. The user application code is responsible for general initialization of clock sources, pin multiplexers, and peripheral registers related to the communication speed. Such initialization should be done before calling the FMSTR_Init function.

It is recommended to develop the user application using one of the Software Development Kits (SDKs) available from third parties or directly from NXP, such as MCUXpresso SDK, MCUXpresso IDE, and related tools. This approach simplifies the general configuration process significantly.

MCUXpresso SDK The MCUXpresso SDK is a software package provided by NXP which contains the device initialization code, linker files, and software drivers with example applications for the NXP family of MCUs. The MCUXpresso Config Tools may be used to generate the clock-setup and pin-multiplexer setup code suitable for the selected processor.

The MCUXpresso SDK also contains this FreeMASTER communication driver as a "middleware" component which may be downloaded along with the example applications from https://mcuxpresso.nxp.com/en/welcome.

MCUXpresso SDK on GitHub

The FreeMASTER communication driver is also released as one of the middleware components of the MCUXpresso SDK on the GitHub. This release enables direct integration of the FreeMASTER source code Git repository into a target applications including Zephyr applications.

Related links:

- The official FreeMASTER middleware repository.
- Online version of this document

FreeMASTER in Zephyr

The FreeMASTER middleware repository can be used with MCUXpresso SDK as well as a Zephyr module. Zephyr-specific samples which include examples of Kconfig and Device Tree configurations for Serial, USB and Network communications are available in separate repository. West manifest in this sample repository fetches the full Zephyr package including the FreeMASTER middleware repository used as a Zephyr module.

Example applications MCUX SDK Example applications

There are several example applications available for each supported MCU platform.

- **fmstr_uart** demonstrates a plain serial transmission, typically connecting to a computer's physical or virtual COM port. The typical transmission speed is 115200 bps.
- **fmstr_can** demonstrates CAN bus communication. This requires a suitable CAN interface connected to the computer and interconnected with the target MCU using a properly terminated CAN bus. The typical transmission speed is 500 kbps. A FreeMASTER-over-CAN communication plug-in must be used.
- **fmstr_usb_cdc** uses an on-chip USB controller to implement a CDC communication class. It is connected directly to a computer's USB port and creates a virtual COM port device. The typical transmission speed is above 1 Mbps.
- **fmstr_net** demonstrates the Network communication over UDP or TCP protocol. Existing examples use lwIP stack to implement the communication, but in general, it shall be possible to use any other TCP/IP stack to achieve the same functionality.
- **fmstr_wifi** is the fmstr_net application modified to use a WiFi network interface instead of a wired Ethernet connection.
- **fmstr_rtt** demonstrates the communication over SEGGER J-Link RTT interface. Both fmstr_net and fmstr_rtt examples require the FreeMASTER TCP/UDP communication plug-in to be used on the PC host side.
- **fmstr_eonce** uses the real-time data unit on the JTAG EOnCE module of the 56F800E family to implement pseudo-serial communication over the JTAG port. The typical transmission speed is around 10 kbps. This communication requires FreeMASTER JTAG/EOnCE communication plug-in.
- **fmstr_pdbdm** uses JTAG or BDM debugging interface to access the target RAM directly while the CPU is running. Note that such approach can be used with any MCU application, even without any special driver code. The computer reads from and writes into the RAM directly without CPU intervention. The Packet-Driven BDM (PD-BDM) communication uses the same memory access to exchange command and response frames. With PD-BDM, the FreeMASTER tool is able to go beyond basic memory read/write operations and accesses also advanced features like Recorder, TSA, or Pipes. The typical transmission speed is around 10 kbps. A PD-BDM communication plug-in must be used in FreeMASTER and configured properly for the selected debugging interface. Note that this communication cannot be used while a debugging interface is used by a debugger session.
- **fmstr_any** is a special example application which demonstrates how the NXP MCUXpresso Config Tools can be used to configure pins, clocks, peripherals, interrupts, and even the FreeMASTER "middleware" driver features in a graphical and user friendly way. The user can switch between the Serial, CAN, and other ways of communication and generate the required initialization code automatically.

Zephyr sample spplications

Zephyr sample applications demonstrate Kconfig and Device Tree configuration which configure the FreeMASTER middleware module for a selected communication option (Serial, CAN, Network or RTT).

Refer to *readme.md* files in each sample directory for description of configuration options required to implement FreeMASTER connectivity.

Description

This section shows how to add the FreeMASTER Communication Driver into application and how to configure the connection to the FreeMASTER visualization tool.

Features The FreeMASTER driver implements the FreeMASTER protocol V4 and provides the following features which may be accessed using the FreeMASTER visualization tool:

- Read/write access to any memory location on the target.
- Optional password protection of the read, read/write, and read/write/flash access levels.
- Atomic bit manipulation on the target memory (bit-wise write access).
- Optimal size-aligned access to memory which is also suitable to access the peripheral register space.
- Oscilloscope access—real-time access to target variables. The sample rate may be limited by the communication speed.
- Recorder— access to the fast transient recorder running on the board as a part of the FreeMASTER driver. The sample rate is only limited by the MCU CPU speed. The length of the data recorded depends on the amount of available memory.
- Multiple instances of Oscilloscopes and Recorders without the limitation of maximum number of variables.
- Application commands—high-level message delivery from the PC to the application.
- TSA tables—describing the data types, variables, files, or hyperlinks exported by the target application. The TSA newly supports also non-memory mapped resources like external EEPROM or SD Card files.
- Pipes—enabling the buffered stream-oriented data exchange for a general-purpose terminal-like communication, diagnostic data streaming, or other data exchange.

The FreeMASTER driver features:

- Full FreeMASTER protocol V4 implementation with a new V4 style of CRC used.
- Layered approach supporting Serial, CAN, Network, PD-BDM, and other transports.
- Layered low-level Serial transport driver architecture enabling to select UART, LPUART, USART, and other physical implementations of serial interfaces, including USB-CDC.
- Layered low-level CAN transport driver architecture enabling to select FlexCAN, msCAN, MCAN, and other physical implementations of the CAN interface.
- Layered low-level Networking transport enabling to select TCP, UDP or J-Link RTT communication.
- TSA support to write-protect memory regions or individual variables and to deny the access to the unsafe memory.
- The pipe callback handlers are invoked whenever new data is available for reading from the pipe.
- Two Serial Single-Wire modes of operation are enabled. The “external” mode has the RX and TX shorted on-board. The “true” single-wire mode interconnects internally when the MCU or UART modules support it.

The following sections briefly describe all FreeMASTER features implemented by the driver. See the PC-based FreeMASTER User Manual for more details on how to use the features to monitor, tune, or control an embedded application.

Board Detection

The FreeMASTER protocol V4 defines the standard set of configuration values which the host PC tool reads to identify the target and to access other target resources properly. The configuration includes the following parameters:

- Version of the driver and the version of the protocol implemented.
- MTU as the Maximum size of the Transmission Unit (for example; communication buffer size).
- Application name, description, and version strings.

- Application build date and time as a string.
- Target processor byte ordering (little/big endian).
- Protection level that requires password authentication.
- Number of the Recorder and Oscilloscope instances.
- RAM Base Address for optimized memory access commands.

Memory Read

This basic feature enables the host PC to read any data memory location by specifying the address and size of the required memory area. The device response frame must be shorter than the MTU to fit into the outgoing communication buffer. To read a device memory of any size, the host uses the information retrieved during the Board Detection and splits the large-block request to multiple partial requests.

The driver uses size-aligned operations to read the target memory (for example; uses proper read-word instruction when an address is aligned to 4 bytes).

Memory Write

Similarly to the Memory Read operation, the Memory Write feature enables to write to any RAM memory location on the target device. A single write command frame must be shorter than the MTU to fit into the target communication buffer. Larger requests must be split into smaller ones.

The driver uses size-aligned operations to write to the target memory (for example; uses proper write-word instruction when an address is aligned to 4 bytes).

Masked Memory Write

To implement the write access to a single bit or a group of bits of target variables, the Masked Memory Write feature is available in the FreeMASTER protocol and it is supported by the driver using the Read-Modify-Write approach.

Be careful when writing to bit fields of volatile variables that are also modified in an application interrupt. The interrupt may be serviced in the middle of a read-modify-write operation and it may cause data corruption.

Oscilloscope

The protocol and driver enables any number of variables to be read at once with a single request from the host. This feature is called Oscilloscope and the FreeMASTER tool uses it to display a real-time graph of variable values.

The driver can be configured to support any number of Oscilloscope instances and enable simultaneously running graphs to be displayed on the host computer screen.

Recorder

The protocol enables the host to select target variables whose values are then periodically recorded into a dedicated on-board memory buffer. After such data sampling stops (either on a host request or by evaluating a threshold-crossing condition), the data buffer is downloaded to the host and displayed as a graph. The data sampling rate is not limited by the speed of the communication line, so it enables displaying the variable transitions in a very high resolution.

The driver can be configured to support multiple Recorder instances and enable multiple recorder graphs to be displayed on the host screen. Having multiple recorders also enables setting the recording point differently for each instance. For example; one instance may be recording data in a general timer interrupt while another instance may record at a specific control algorithm time in the PWM interrupt.

TSA

With the TSA feature, data types and variables can be described directly in the application source code. Such information is later provided to the FreeMASTER tool which may use it instead of reading symbol data from the application ELF executable file.

The information is encoded as so-called TSA tables which become direct part of the application code. The TSA tables contain descriptors of variables that shall be visible to the host tool. The descriptors can describe the memory areas by specifying the address and size of the memory block or more conveniently using the C variable names directly. Different set of TSA descriptors can be used to encode information about the structure types, unions, enumerations, or arrays.

The driver also supports special types of TSA table entries to describe user resources like external EEPROM and SD Card files, memory-mapped files, virtual directories, web URL hyperlinks, and constant enumerations.

TSA Safety

When the TSA is enabled in the application, the TSA Safety can be enabled and validate the memory accesses directly by the embedded-side driver. When the TSA Safety is turned on, any memory request received from the host is validated and accepted only if it belongs to a TSA-described object. The TSA entries can be declared as Read-Write or Read-Only so that the driver can actively deny the write access to the Read-Only objects.

Application commands

The Application Commands are high-level messages that can be delivered from the PC Host to the embedded application for further processing. The embedded application can either poll the status, or be called back when a new Application Command arrives to be processed. After the embedded application acknowledges that the command is handled, the host receives the Result Code and reads the other return data from memory. Both the Application Commands and the Result Codes are specific to a given application and it is user's responsibility to define them. The FreeMASTER protocol and the FreeMASTER driver only implement the delivery channel and a set of API calls to enable the Application Command processing in general.

Pipes

The Pipes enable buffered and stream-oriented data exchange between the PC Host and the target application. Any pipe can be written to and read from at both ends (either on the PC or the MCU). The data transmission is acknowledged using the special FreeMASTER protocol commands. It is guaranteed that the data bytes are delivered from the writer to the reader in a proper order and without losses.

Serial single-wire operation

The MCU Serial Communication Driver natively supports normal dual-wire operation. Because the protocol is half-duplex only, the driver can also operate in two single-wire modes:

- "External" single-wire operation where the Receiver and Transmitter pins are shorted on the board. This mode is supported by default in the MCU driver because the Receiver and Transmitter units are enabled or disabled whenever needed. It is also easy to extend this operation for the RS485 communication.
- "True" single-wire mode which uses only a single pin and the direction switching is made by the UART module. This mode of operation must be enabled by defining the FMSTR_SERIAL_SINGLEWIRE configuration option.

Multi-session support

With networking interface it is possible for multiple clients to access the target MCU simultaneously. Reading and writing of target memory is processed atomically so there is no risk of data

corruption. The state-full resources such as Recorders or Oscilloscopes are locked to a client session upon first use and access is denied to other clients until lock is released..

Zephyr-specific

Dedicated communication task

FreeMASTER communication may run isolated in a dedicated task. The task automates the FMSTR_Init and FMSTR_Poll calls together with periodic activities enabling the FreeMASTER UI to fetch information about tasks and CPU utilization. The task can be started automatically or manually, and it must be assigned a priority to be able to react on interrupts and other communication events. Refer to Zephyr FreeMASTER sample applications which all use this communication task.

Zephyr shell and logging over FreeMASTER pipe

FreeMASTER implements a shell backend which may use FreeMASTER pipe as a I/O terminal and logging output. Refer to Zephyr FreeMASTER sample applications which all use this feature.

Automatic TSA tables

TSA tables can be declared as “automatic” in Zephyr which make them automatically registered in the table list. This may be very useful when there are many TSA tables or when the tables are defined in different (often unrelated) libraries linked together. In this case user does not need to build a list of all tables manually.

Driver files The driver source files can be found in a top-level src folder, further divided into the sub-folders:

- ***src/platforms*** platform-specific folder—one folder exists for each supported processor platform (for example; 32-bit Little Endian platform). Each such folder contains a platform header file with data types and a code which implements the potentially platform-specific operations, such as aligned memory access.
- ***src/common*** folder—contains the common driver source files shared by the driver for all supported platforms. All the *.c* files must be added to the project, compiled, and linked together with the application.
  - *freemaster.h* - master driver header file, which declares the common data types, macros, and prototypes of the FreeMASTER driver API functions.
  - *freemaster_cfg.h.example* - this file can serve as an example of the FreeMASTER driver configuration file. Save this file into a project source code folder and rename it to *freemaster_cfg.h*. The FreeMASTER driver code includes this file to get the project-specific configuration options and to optimize the compilation of the driver.
  - *freemaster_defcfg.h* - defines the default values for each FreeMASTER configuration option if the option is not set in the *freemaster_cfg.h* file.
  - *freemaster_protocol.h* - defines the FreeMASTER protocol constants used internally by the driver.
  - *freemaster_protocol.c* - implements the FreeMASTER protocol decoder and handles the basic Get Configuration Value, Memory Read, and Memory Write commands.
  - *freemaster_rec.c* - handles the Recorder-specific commands and implements the Recorder sampling and triggering routines. When the Recorder is disabled by the FreeMASTER driver configuration file, this file only compiles to empty API functions.
  - *freemaster_scope.c* - handles the Oscilloscope-specific commands. If the Oscilloscope is disabled by the FreeMASTER driver configuration file, this file compiles as void.

  - *freemaster_pipes.c* - implements the Pipes functionality when the Pipes feature is enabled.
  - *freemaster_appcmd.c* - handles the communication commands used to deliver and execute the Application Commands within the context of the embedded application. When the Application Commands are disabled by the FreeMASTER driver configuration file, this file only compiles to empty API functions.
  - *freemaster_tsa.c* - handles the commands specific to the TSA feature. This feature enables the FreeMASTER host tool to obtain the TSA memory descriptors declared in the embedded application. If the TSA is disabled by the FreeMASTER driver configuration file, this file compiles as void.
  - *freemaster_tsa.h* - contains the declaration of the macros used to define the TSA memory descriptors. This file is indirectly included into the user application code (via *freemaster.h*).
  - *freemaster_sha.c* - implements the SHA-1 hash code used in the password authentication algorithm.
  - *freemaster_private.h* - contains the declarations of functions and data types used internally in the driver. It also contains the C pre-processor statements to perform the compile-time verification of the user configuration provided in the *freemaster_cfg.h* file.
  - *freemaster_serial.c* - implements the serial protocol logic including the CRC, FIFO queuing, and other communication-related operations. This code calls the functions of the low-level communication driver indirectly via a character-oriented API exported by the specific low-level driver.
  - *freemaster_serial.h* - defines the low-level character-oriented Serial API.
  - *freemaster_can.c* - implements the CAN protocol logic including the CAN message preparation, signalling using the first data byte in the CAN frame, and other communication-related operations. This code calls the functions of the low-level communication driver indirectly via a message-oriented API exported by the specific low-level driver.
  - *freemaster_can.h* - defines the low-level message-oriented CAN API.
  - *freemaster_net.c* - implements the Network protocol transport logic including multiple session management code.
  - *freemaster_net.h* - definitions related to the Network transport.
  - *freemaster_pdbdm.c* - implements the packet-driven BDM communication buffer and other communication-related operations.
  - *freemaster_utils.c* - aligned memory copy routines, circular buffer management and other utility functions
  - *freemaster_utils.h* - definitions related to utility code.

- ***src/drivers/[sdk]/serial*** - contains the code related to the serial communication implemented using one of the supported SDK frameworks.
  - *freemaster_serial_XXX.c* and *.h* - implement low-level access to the communication peripheral registers. Different files exist for the UART, LPUART, USART, and other kinds of Serial communication modules.
- ***src/drivers/[sdk]/can*** - contains the code related to the serial communication implemented using one of the supported SDK frameworks.
  - *freemaster_XXX.c* and *.h* - implement low-level access to the communication peripheral registers. Different files exist for the FlexCAN, msCAN, MCAN, and other kinds of CAN communication modules.

- ***src/drivers/[sdk]/network*** - contains low-level code adapting the FreeMASTER Network transport to an underlying TCP/IP or RTT stack.
  - *freemaster_net_lwip_tcp.c* and *_udp.c* - default networking implementation of TCP and UDP transports using lwIP stack.
  - *freemaster_net_segger_rtt.c* - implementation of network transport using Segger J-Link RTT interface

Driver configuration The driver is configured using a single header file (*freemaster_cfg.h*). Create this file and save it together with other project source files before compiling the driver code. All FreeMASTER driver source files include the *freemaster_cfg.h* file and use the macros defined here for the conditional and parameterized compilation. The C compiler must locate the configuration file when compiling the driver files. Typically, it can be achieved by putting this file into a folder where the other project-specific included files are stored.

As a starting point to create the configuration file, get the *freemaster_cfg.h.example* file, rename it to *freemaster_cfg.h*, and save it into the project area.

Note: It is NOT recommended to leave the *freemaster_cfg.h* file in the FreeMASTER driver source code folder. The configuration file must be placed at a project-specific location, so that it does not affect the other applications that use the same driver.

Configurable items This section describes the configuration options which can be defined in *freemaster_cfg.h*.

Interrupt modes

```
#define FMSTR_LONG_INTR   [0|1]
#define FMSTR_SHORT_INTR  [0|1]
#define FMSTR_POLL_DRIVEN [0|1]
```

Value Type

boolean (0 or 1)

Description

Exactly one of the three macros must be defined to non-zero. The others must be defined to zero or left undefined. The non-zero-defined constant selects the interrupt mode of the driver. See *Driver interrupt modes*.

- FMSTR_LONG_INTR — long interrupt mode
- FMSTR_SHORT_INTR — short interrupt mode
- FMSTR_POLL_DRIVEN — poll-driven mode

Note: Some options may not be supported by all communication interfaces. For example, the FMSTR_SHORT_INTR option is not supported by the USB_CDC interface.

Protocol transport

```
#define FMSTR_TRANSPORT [identifier]
```

Value Type

Driver identifiers are structure instance names defined in FreeMASTER source code. Specify one of existing instances to make use of the protocol transport.

Description

Use one of the pre-defined constants, as implemented by the FreeMASTER code. The current driver supports the following transports:

- **FMSTR_SERIAL** - serial communication protocol
- **FMSTR_CAN** - using CAN communication
- **FMSTR_PDBDM** - using packet-driven BDM communication
- **FMSTR_NET** - network communication using TCP or UDP protocol

Serial transport

This section describes configuration parameters used when serial transport is used:

```
#define FMSTR_TRANSPORT FMSTR_SERIAL
```

FMSTR_SERIAL_DRV

Select what low-level driver interface will be used when implementing the Serial communication.

```
#define FMSTR_SERIAL_DRV [identifier]
```

Value Type

Driver identifiers are structure instance names defined in FreeMASTER drivers code. Specify one of existing serial driver instances.

Description

When using MCUXpresso SDK, use one of the following constants (see */drivers/mcuxsdk/serial* implementation):

- **FMSTR_SERIAL_MCUX_UART** - UART driver
- **FMSTR_SERIAL_MCUX_LPUART** - LPUART driver
- **FMSTR_SERIAL_MCUX_USART** - USART driver
- **FMSTR_SERIAL_MCUX_MINIUSART** - miniUSART driver
- **FMSTR_SERIAL_MCUX_QSCI** - DSC QSCI driver
- **FMSTR_SERIAL_MCUX_USB** - USB/CDC class driver (also see code in the */support/mcuxsdk_usb* folder)
- **FMSTR_SERIAL_56F800E_EONCE** - DSC JTAG EOnCE driver

Other SDKs or BSPs may define custom low-level driver interface structure which may be used as FMSTR_SERIAL_DRV. For example:

- **FMSTR_SERIAL_DREG_UART** - demonstrates the low-level interface implemented without the MCUXpresso SDK and using direct access to peripheral registers.

FMSTR_SERIAL_BASE

```
#define FMSTR_SERIAL_BASE [address|symbol]
```

Value Type

Optional address value (numeric or symbolic)

Description

Specify the base address of the UART, LPUART, USART, or other serial peripheral module to be used for the communication. This value is not defined by default. User application should call FMSTR_SetSerialBaseAddress() to select the peripheral module.

FMSTR_COMM_BUFFER_SIZE

```
#define FMSTR_COMM_BUFFER_SIZE [number]
```

Value Type

0 or a value in range 32...255

Description

Specify the size of the communication buffer to be allocated by the driver.
Default value, which suits all driver features, is used when this option is defined as 0.

FMSTR_COMM_RQUEUE_SIZE

```
#define FMSTR_COMM_RQUEUE_SIZE [number]
```

Value Type

Value in range 0...255

Description

Specify the size of the FIFO receiver queue used to quickly receive and store characters in the FMSTR_SHORT_INTR interrupt mode.
The default value is 32 B.

FMSTR_SERIAL_SINGLEWIRE

```
#define FMSTR_SERIAL_SINGLEWIRE [0|1]
```

Value Type

Boolean 0 or 1.

Description

Set to non-zero to enable the “True” single-wire mode which uses a single MCU pin to communicate. The low-level driver enables the pin direction switching when the MCU peripheral supports it.

CAN Bus transport

This section describes configuration parameters used when CAN transport is used:

```
#define FMSTR_TRANSPORT FMSTR_CAN
```

FMSTR_CAN_DRV

Select what low-level driver interface will be used when implementing the CAN communication.

```
#define FMSTR_CAN_DRV [identifier]
```

Value Type

Driver identifiers are structure instance names defined in FreeMASTER drivers code. Specify one of existing CAN driver instances.

Description

When using MCUXpresso SDK, use one of the following constants (see */drivers/mcuxsdk/can implementation*):

- **FMSTR_CAN_MCUX_FLEXCAN** - FlexCAN driver
- **FMSTR_CAN_MCUX_MCAN** - MCAN driver
- **FMSTR_CAN_MCUX_MSCAN** - msCAN driver
- **FMSTR_CAN_MCUX_DSCFLEXCAN** - DSC FlexCAN driver
- **FMSTR_CAN_MCUX_DSCMSCAN** - DSC msCAN driver

Other SDKs or BSPs may define the custom low-level driver interface structure which may be used as FMSTR_CAN_DRV.

FMSTR_CAN_BASE

```
#define FMSTR_CAN_BASE [address|symbol]
```

Value Type

Optional address value (numeric or symbolic)

Description

Specify the base address of the FlexCAN, msCAN, or other CAN peripheral module to be used for the communication. This value is not defined by default. User application should call FMSTR_SetCanBaseAddress() to select the peripheral module.

FMSTR_CAN_CMDID

```
#define FMSTR_CAN_CMDID [number]
```

Value Type

CAN identifier (11-bit or 29-bit number)

Description

CAN message identifier used for FreeMASTER commands (direction from PC Host tool to target application). When declaring 29-bit identifier, combine the numeric value with FMSTR_CAN_EXTID bit. Default value is 0x7AA.

FMSTR_CAN_RSPID

```
#define FMSTR_CAN_RSPID [number]
```

Value Type

CAN identifier (11-bit or 29-bit number)

Description

CAN message identifier used for responding messages (direction from target application to PC Host tool). When declaring 29-bit identifier, combine the numeric value with FMSTR_CAN_EXTID bit. Note that both *CMDID* and *RSPID* values may be the same. Default value is 0x7AA.

FMSTR_FLEXCAN_TXMB

```
#define FMSTR_FLEXCAN_TXMB [number]
```

Value Type

Number in range of 0..N where N is number of CAN message-buffers supported by HW module.

Description

Only used when the FlexCAN low-level driver is used. Define the FlexCAN message buffer for CAN frame transmission. Default value is 0.

FMSTR_FLEXCAN_RXMB

```
#define FMSTR_FLEXCAN_RXMB [number]
```

Value Type

Number in range of 0..N where N is number of CAN message-buffers supported by HW module.

Description

Only used when the FlexCAN low-level driver is used. Define the FlexCAN message buffer for CAN frame reception. Note that the FreeMASTER driver may also operate with a common message buffer used by both TX and RX directions. Default value is 1.

Network transport

This section describes configuration parameters used when Network transport is used:

```
#define FMSTR_TRANSPORT FMSTR_NET
```

FMSTR_NET_DRV

Select network interface implementation.

```
#define FMSTR_NET_DRV [identifier]
```

Value Type

Identifiers are structure instance names defined in FreeMASTER drivers code. Specify one of existing NET driver instances.

Description

When using MCUXpresso SDK, use one of the following constants (see */drivers/mcuxsdk/network implementation*):

- **FMSTR_NET_LWIP_TCP** - TCP communication using lwIP stack
- **FMSTR_NET_LWIP_UDP** - UDP communication using lwIP stack
- **FMSTR_NET_SEGGER_RTT** - Communication using SEGGER J-Link RTT interface

Other SDKs or BSPs may define the custom networking interface which may be used as FMSTR_CAN_DRV.

Add another row below:

FMSTR_NET_PORT

```
#define FMSTR_NET_PORT [number]
```

Value Type

TCP or UDP port number (short integer)

Description

Specifies the server port number used by TCP or UDP protocols.

FMSTR_NET_BLOCKING_TIMEOUT

```
#define FMSTR_NET_BLOCKING_TIMEOUT [number]
```

Value Type

Timeout as number of milliseconds

Description

This value specifies a timeout in milliseconds for which the network socket operations may block the execution inside *FMSTR_Poll*. This may be set high (e.g. 250) when a dedicated RTOS task is used to handle FreeMASTER protocol polling. Set to a lower value when the polling task is also responsible for other operations. Set to 0 to attempt to use non-blocking socket operations.

FMSTR_NET_AUTODISCOVERY

```
#define FMSTR_NET_AUTODISCOVERY [0|1]
```

Value Type

Boolean 0 or 1.

Description

This option enables the FreeMASTER driver to use a separate UDP socket to broadcast auto-discovery messages to network. This helps the FreeMASTER tool to discover the target device address, port and protocol options.

Debugging options

FMSTR_DISABLE

```
#define FMSTR_DISABLE [0|1]
```

Value Type

boolean (0 or 1)

Description

Define as non-zero to disable all FreeMASTER features, exclude the driver code from build, and compile all its API functions empty. This may be useful to remove FreeMASTER without modifying any application source code. Default value is 0 (false).

FMSTR_DEBUG_TX

```
#define FMSTR_DEBUG_TX [0|1]
```

Value Type

Boolean 0 or 1.

Description

Define as non-zero to enable the driver to periodically transmit test frames out on the selected communication interface (SCI or CAN). With the debug transmission enabled, it is simpler to detect problems in the baudrate or other communication configuration settings.

The test frames are transmitted until the first valid command frame is received from the PC Host tool. The test frame is a valid error status frame, as defined by the protocol format. On the serial line, the test frame consists of three printable characters (+©W) which are easy to capture using the serial terminal tools.

This feature requires the FMSTR_Poll() function to be called periodically. Default value is 0 (false).

FMSTR_APPLICATION_STR

```
#define FMSTR_APPLICATION_STR
```

Value Type

String.

Description

Name of the application visible in FreeMASTER host application.

Memory access

FMSTR_USE_READMEM

```
#define FMSTR_USE_READMEM [0|1]
```

Value Type

Boolean 0 or 1.

Description

Define as non-zero to implement the Memory Read command and enable FreeMASTER to have read access to memory and variables. The access can be further restricted by using a TSA feature. Default value is 1 (true).

FMSTR_USE_WRITEMEM

```
#define FMSTR_USE_WRITEMEM [0|1]
```

Value Type

Boolean 0 or 1.

Description

Define as non-zero to implement the Memory Write command.
The default value is 1 (true).

Oscilloscope options

FMSTR_USE_SCOPE

```
#define FMSTR_USE_SCOPE [number]
```

Value Type

Integer number.

Description

Number of Oscilloscope instances to be supported. Set to 0 to disable the Oscilloscope feature.
Default value is 0.

FMSTR_MAX_SCOPE_VARS

```
#define FMSTR_MAX_SCOPE_VARS [number]
```

Value Type

Integer number larger than 2.

Description

Number of variables to be supported by each Oscilloscope instance.
Default value is 8.

Recorder options

FMSTR_USE_RECORDER

```
#define FMSTR_USE_RECORDER [number]
```

Value Type

Integer number.

Description

Number of Recorder instances to be supported. Set to 0 to disable the Recorder feature.
Default value is 0.

FMSTR_REC_BUFF_SIZE

```
#define FMSTR_REC_BUFF_SIZE [number]
```

Value Type

Integer number larger than 2.

Description

Defines the size of the memory buffer used by the Recorder instance #0.
Default: not defined, user shall call 'FMSTR_RecorderCreate()" API function to specify this parameter in run time.

FMSTR_REC_TIMEBASE

```
#define FMSTR_REC_TIMEBASE [time specification]
```

Value Type

Number (nanoseconds time).

Description

Defines the base sampling rate in nanoseconds (sampling speed) Recorder instance #0.

Use one of the following macros:

- FMSTR_REC_BASE_SECONDS(x)
- FMSTR_REC_BASE_MILLISEC(x)
- FMSTR_REC_BASE_MICROSEC(x)
- FMSTR_REC_BASE_NANOSEC(x)

Default: not defined, user shall call 'FMSTR_RecorderCreate()" API function to specify this parameter in run time.

FMSTR_REC_FLOAT_TRIG

```
#define FMSTR_REC_FLOAT_TRIG [0|1]
```

Value Type

Boolean 0 or 1.

Description

Define as non-zero to implement the floating-point triggering. Be aware that floating-point triggering may grow the code size by linking the floating-point standard library.

Default value is 0 (false).

Application Commands options

FMSTR_USE_APPCMD

```
#define FMSTR_USE_APPCMD [0|1]
```

Value Type

Boolean 0 or 1.

Description

Define as non-zero to implement the Application Commands feature.
Default value is 0 (false).

FMSTR_APPCMD_BUFF_SIZE

```
#define FMSTR_APPCMD_BUFF_SIZE [size]
```

Value Type

Numeric buffer size in range 1..255

Description

The size of the Application Command data buffer allocated by the driver. The buffer stores the (optional) parameters of the Application Command which waits to be processed.

FMSTR_MAX_APPCMD_CALLS

```
#define FMSTR_MAX_APPCMD_CALLS [number]
```

Value Type

Number in range 0..255

Description

The number of different Application Commands that can be assigned a callback handler function using FMSTR_RegisterAppCmdCall(). Default value is 0.

TSA options

FMSTR_USE_TSA

```
#define FMSTR_USE_TSA [0|1]
```

Value Type

Boolean 0 or 1.

Description

Enable the FreeMASTER TSA feature to be used. With this option enabled, the TSA tables defined in the applications are made available to the FreeMASTER host tool.
Default value is 0 (false).

FMSTR_USE_TSA_SAFETY

```
#define FMSTR_USE_TSA_SAFETY [0|1]
```

Value Type

Boolean 0 or 1.

Description

Enable the memory access validation in the FreeMASTER driver. With this option, the host tool is not able to access the memory which is not described by at least one TSA descriptor. Also a write access is denied for objects defined as read-only in TSA tables.
Default value is 0 (false).

FMSTR_USE_TSA_INROM

```
#define FMSTR_USE_TSA_INROM [0|1]
```

Value Type

Boolean 0 or 1.

Description

Declare all TSA descriptors as *const*, which enables the linker to put the data into the flash memory. The actual result depends on linker settings or the linker commands used in the project.
Default value is 0 (false).

FMSTR_USE_TSA_DYNAMIC

```
#define FMSTR_USE_TSA_DYNAMIC [0|1]
```

Value Type

Boolean 0 or 1.

Description

Enable runtime-defined TSA entries to be added to the TSA table by the FMSTR_SetUpTsaBuff() and FMSTR_TsaAddVar() functions.
Default value is 0 (false).

Pipes options

FMSTR_USE_PIPES

```
#define FMSTR_USE_PIPES [0|1]
```

Value Type

Boolean 0 or 1.

Description

Enable the FreeMASTER Pipes feature to be used.
Default value is 0 (false).

FMSTR_MAX_PIPES_COUNT

```
#define FMSTR_MAX_PIPES_COUNT [number]
```

Value Type

Number in range 1..63.

Description

The number of simultaneous pipe connections to support.
The default value is 1.

Driver interrupt modes To implement the communication, the FreeMASTER driver handles the Serial or CAN module's receive and transmit requests. Use the *freemaster_cfg.h* configuration file to select whether the driver processes the communication automatically in the interrupt service routine handler or if it only polls the status of the module (typically during the application idle time).

This section describes each of the interrupt mode in more details.

Completely Interrupt-Driven operation

Activated using:

```
#define FMSTR_LONG_INTR 1
```

In this mode, both the communication and the FreeMASTER protocol decoding is done in the *FMSTR_SerialIsr*, *FMSTR_CanIsr*, or other interrupt service routine. Because the protocol execution may be a lengthy task (especially with the TSA-Safety enabled) it is recommended to use this mode only if the interrupt prioritization scheme is possible in the application and the FreeMASTER interrupt is assigned to a lower (the lowest) priority.

In this mode, the application code must register its own interrupt handler for all interrupt vectors related to the selected communication interface and call the FMSTR_SerialIsr or FMSTR_CanIsr functions from that handler.

Mixed Interrupt and Polling Modes

Activated using:

```
#define FMSTR_SHORT_INTR 1
```

In this mode, the communication processing time is split between the interrupt routine and the main application loop or task. The raw communication is handled by the *FMSTR_SerialIsr, FMSTR_CanIsr*, or other interrupt service routine, while the protocol decoding and execution is handled by the *FMSTR_Poll* routine. Call *FMSTR_Poll* during the idle time in the application main loop.

The interrupt processing in this mode is relatively fast and deterministic. Upon a serial-receive event, the received character is only placed into a FIFO-like queue and it is not further processed. Upon a CAN receive event, the received frame is stored into a receive buffer. When transmitting, the characters are fetched from the prepared transmit buffer.

In this mode, the application code must register its own interrupt handler for all interrupt vectors related to the selected communication interface and call the *FMSTR_SerialIsr* or *FMSTR_CanIsr* functions from that handler.

When the serial interface is used as the serial communication interface, ensure that the *FMSTR_Poll* function is called at least once per *N* character time periods. *N* is the length of the FreeMASTER FIFO queue (*FMSTR_COMM_RQUEUE_SIZE*) and the character time is the time needed to transmit or receive a single byte over the SCI line.

Completely Poll-driven

```
#define FMSTR_POLL_DRIVEN 1
```

In this mode, both the communication and the FreeMASTER protocol decoding are done in the *FMSTR_Poll* routine. No interrupts are needed and the *FMSTR_SerialIsr*, *FMSTR_CanIsr*, and similar handlers compile to an empty code.

When using this mode, ensure that the *FMSTR_Poll* function is called by the application at least once per the serial "character time" which is the time needed to transmit or receive a single character.

In the latter two modes (*FMSTR_SHORT_INTR* and *FMSTR_POLL_DRIVEN*), the protocol handling takes place in the FMSTR_Poll routine. An application interrupt can occur in the middle of the Read Memory or Write Memory commands' execution and corrupt the variable being accessed by the FreeMASTER driver. In these two modes, some issues or glitches may occur when using FreeMASTER to visualize or monitor volatile variables modified in interrupt servicing code.

The same issue may appear even in the full interrupt mode (FMSTR_LONG_INTR), if volatile variables are modified in the interrupt code with a priority higher than the priority of the communication interrupt.

Data types Simple portability was one of the main requirements when writing the FreeMASTER driver. This is why the driver code uses the privately-declared data types and the vast majority of the platform-dependent code is separated in the platform-dependent source files. The data types used in the driver API are all defined in the platform-specific header file.

To prevent name conflicts with the symbols used in the application, all data types, macros, and functions have the FMSTR_ prefix. The only global variables used in the driver are the transport and low-level API structures exported from the driver-implementation layer to upper layers. Other than that, all private variables are declared as static and named using the fmstr_ prefix.

Communication interface initialization The FreeMASTER driver does not perform neither the initialization nor the configuration of the peripheral module that it uses to communicate. It is the application startup code responsibility to configure the communication module before the FreeMASTER driver is initialized by the FMSTR_Init call.

When the Serial communication module is used as the FreeMASTER communication interface, configure the UART receive and transmit pins, the serial communication baud rate, parity (no-parity), the character length (eight bits), and the number of stop bits (one) before initializing the FreeMASTER driver. For either the long or the short interrupt modes of the driver (see *Driver interrupt modes*), configure the interrupt controller and register an application-specific interrupt handler for all interrupt sources related to the selected serial peripheral module. Call the FMSTR_SerialIsr function from the application handler.

When a CAN module is used as the FreeMASTER communication interface, configure the CAN receive and transmit pins and the CAN module bit rate before initializing the FreeMASTER driver. For either the long or the short interrupt modes of the driver (see *Driver interrupt modes*), configure the interrupt controller and register an application-specific interrupt handler for all interrupt sources related to the selected CAN peripheral module. Call the FMSTR_CanIsr function from the application handler.

Note: It is not necessary to enable or unmask the serial nor the CAN interrupts before initializing the FreeMASTER driver. The driver enables or disables the interrupts and communication lines, as required during runtime.

FreeMASTER Recorder calls When using the FreeMASTER Recorder in the application (FMSTR_USE_RECORDER > 0), call the FMSTR_RecorderCreate function early after FMSTR_Init to set

up each recorder instance to be used in the application. Then call the FMSTR_Recorder function periodically in the code where the data recording should occur. A typical place to call the Recorder routine is at the timer or PWM interrupts, but it can be anywhere else. The example applications provided together with the driver code call the FMSTR_Recorder in the main application loop.

In applications where FMSTR_Recorder is called periodically with a constant period, specify the period in the Recorder configuration structure before calling FMSTR_RecorderCreate. This setting enables the PC Host FreeMASTER tool to display the X-axis of the Recorder graph properly scaled for the time domain.

Driver usage Start using or evaluating FreeMASTER by opening some of the example applications available in the driver setup package.

Follow these steps to enable the basic FreeMASTER connectivity in the application:

- Make sure that all **.c* files of the FreeMASTER driver from the *src/common/platforms/[your_platform]* folder are a part of the project. See *Driver files* for more details.
- Configure the FreeMASTER driver by creating or editing the *freemaster_cfg.h* file and by saving it into the application project directory. See *Driver configuration* for more details.
- Include the *freemaster.h* file into any application source file that makes the FreeMASTER API calls.
- Initialize the Serial or CAN modules. Set the baud rate, parity, and other parameters of the communication. Do not enable the communication interrupts in the interrupt mask registers.
- For the FMSTR_LONG_INTR and FMSTR_SHORT_INTR modes, install the application-specific interrupt routine and call the FMSTR_SerialIsr or FMSTR_CanIsr functions from this handler.
- Call the FMSTR_Init function early on in the application initialization code.
- Call the FMSTR_RecorderCreate functions for each Recorder instance to enable the Recorder feature.
- In the main application loop, call the FMSTR_Poll API function periodically when the application is idle.
- For the FMSTR_SHORT_INTR and FMSTR_LONG_INTR modes, enable the interrupts globally so that the interrupts can be handled by the CPU.

Communication troubleshooting The most common problem that causes communication issues is a wrong baud rate setting or a wrong pin multiplexer setting of the target MCU. When a communication between the PC Host running FreeMASTER and the target MCU cannot be established, try enabling the FMSTR_DEBUG_TX option in the *freemaster_cfg.h* file and call the FMSTR_Poll function periodically in the main application task loop.

With this feature enabled, the FreeMASTER driver periodically transmits a test frame through the Serial or CAN lines. Use a logic analyzer or an oscilloscope to monitor the signals at the communication pins of the CPU device to examine whether the bit rate and signal polarity are configured properly.

Driver API

This section describes the driver Application Programmers' Interface (API) needed to initialize and use the FreeMASTER serial communication driver.

Control API There are three key functions to initialize and use the driver.

FMSTR_Init

Prototype

```
FMSTR_BOOL FMSTR_Init(void);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_protocol.c*

Description

This function initializes the internal variables of the FreeMASTER driver and enables the communication interface. This function does not change the configuration of the selected communication module. The hardware module must be initialized before the *FMSTR_Init* function is called.

A call to this function must occur before calling any other FreeMASTER driver API functions.

FMSTR_Poll

Prototype

```
void FMSTR_Poll(void);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_protocol.c*

Description

In the poll-driven or short interrupt modes, this function handles the protocol decoding and execution (see *Driver interrupt modes*). In the poll-driven mode, this function also handles the communication interface with the PC. Typically, the *FMSTR_Poll* function is called during the "idle" time in the main application task loop.

To prevent the receive data overflow (loss) on a serial interface, make sure that the FMSTR_Poll function is called at least once per the time calculated as:

*N * Tchar*

where:

- *N* is equal to the length of the receive FIFO queue (configured by the FMSTR_COMM_RQUEUE_SIZE macro). *N* is 1 for the poll-driven mode.
- *Tchar* is the character time, which is the time needed to transmit or receive a single byte over the SCI line.

Note: In the long interrupt mode, this function typically compiles as an empty function and can still be called. It is worthwhile to call this function regardless of the interrupt mode used in the application. This approach enables a convenient switching between the different interrupt modes only by changing the configuration macros in the *freemaster_cfg.h* file.

FMSTR_SerialIsr / FMSTR_CanIsr

Prototype

```
void FMSTR_SerialIsr(void);
void FMSTR_CanIsr(void);
```

- Declaration: *freemaster.h*
- Implementation: *hw-specific low-level driver C file*

Description

This function contains the interrupt-processing code of the FreeMASTER driver. In long or short interrupt modes (see *Driver interrupt modes*), this function must be called from the application interrupt service routine registered for the communication interrupt vector. On platforms where the communication module uses multiple interrupt vectors, the application should register a handler for all vectors and call this function at each interrupt.

Note: In a poll-driven mode, this function is compiled as an empty function and does not have to be used.

Recorder API FMSTR_RecorderCreate

Prototype

```
FMSTR_BOOL FMSTR_RecorderCreate(FMSTR_INDEX recIndex, FMSTR_REC_BUFF* buffCfg);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_rec.c*

Description

This function registers a recorder instance and enables it to be used by the PC Host tool. Call this function for all recorder instances from 0 to the maximum number defined by the FMSTR_USE_RECORDER configuration option (minus one). An exception to this requirement is the recorder of instance *0* which may be automatically configured by FMSTR_Init when the *freemaster_cfg.h* configuration file defines the *FMSTR_REC_BUFF_SIZE* and *FMSTR_REC_TIMEBASE* options.

For more information, see *Configurable items*.

FMSTR_Recorder

Prototype

```
void FMSTR_Recorder(FMSTR_INDEX recIndex);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_rec.c*

Description

This function takes a sample of the variables being recorded using the FreeMASTER Recorder instance *recIndex*. If the selected Recorder is not active when the *FMSTR_Recorder* function is being called, the function returns immediately. When the Recorder is active, the values of the variables being recorded are copied into the recorder buffer and the trigger conditions are evaluated.

If a trigger condition is satisfied, the Recorder enters the post-trigger mode, where it counts down the follow-up samples (number of *FMSTR_Recorder* function calls) and de-activates the Recorder when the required post-trigger samples are finished.

The *FMSTR_Recorder* function is typically called in the timer or PWM interrupt service routines. This function can also be called in the application main loop (for testing purposes).

FMSTR_RecorderTrigger

Prototype

```
void FMSTR_RecorderTrigger(FMSTR_INDEX recIndex);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_rec.c*

Description

This function forces the Recorder trigger condition to happen, which causes the Recorder to be automatically deactivated after the post-trigger samples are sampled. Use this function in the application code for programmatic control over the Recorder triggering. This can be useful when a more complex triggering conditions need to be used.

Fast Recorder API The Fast Recorder feature is not available in the FreeMASTER driver version 3. This feature was heavily dependent on the target platform and it was only available for the 56F8xxxx DSCs.

TSA Tables When the TSA is enabled in the FreeMASTER driver configuration file (by setting the FMSTR_USE_TSA macro to a non-zero value), it defines the so-called TSA tables in the application. This section describes the macros that must to be used to define the TSA tables.

There can be any number of TSA tables spread across the application source files. There must be always exactly one TSA Table List defined, which informs the FreeMASTER driver about the active TSA tables.

When there is at least one TSA table and one TSA Table List defined in the application, the TSA information automatically appears in the FreeMASTER symbols list. The symbols can then be used to create FreeMASTER variables for visualization or control.

TSA table definition

The TSA table describes the static or global variables together with their address, size, type, and access-protection information. If the TSA-described variables are of a structure type, the TSA table may also describe this type and provide an access to the individual structure members of the variable.

The TSA table definition begins with the FMSTR_TSA_TABLE_BEGIN macro with a *table_id* identifying the table. The *table_id* shall be a valid C-langiage symbol.

```
FMSTR_TSA_TABLE_BEGIN(table_id)
```

After this opening macro, the TSA descriptors are placed using these macros:

```
/* Adding variable descriptors */
FMSTR_TSA_RW_VAR(name, type)  /* read/write variable entry */
FMSTR_TSA_RO_VAR(name, type)  /* read-only variable entry */

/* Description of complex data types */
```

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```
FMSTR_TSA_STRUCT(struct_name) /* structure or union type entry */
FMSTR_TSA_MEMBER(struct_name, member_name, type)  /* structure member entry */

/* Memory blocks */
FMSTR_TSA_RW_MEM(name, type, address, size) /* read/write memory block */
FMSTR_TSA_RO_MEM(name, type, address, size) /* read-only memory block */
```

The table is closed using the FMSTR_TSA_TABLE_END macro:

```
FMSTR_TSA_TABLE_END()
```

TSA descriptor parameters

The TSA descriptor macros accept these parameters:

- *name* — variable name. The variable must be defined before the TSA descriptor references it.
- *type* — variable or member type. Only one of the pre-defined type constants may be used (see below).
- *struct_name* — structure type name. The type must be defined (typedef) before the TSA descriptor references it.
- *member_name* — structure member name.

Note: The structure member descriptors (FMSTR_TSA_MEMBER) must immediately follow the parent structure descriptor (FMSTR_TSA_STRUCT) in the table.

Note: To write-protect the variables in the FreeMASTER driver (FMSTR_TSA_RO_VAR), enable the TSA-Safety feature in the configuration file.

TSA variable types

The table lists *type* identifiers which can be used in TSA descriptors:

Constant	Description
FMSTR_TSA_UINT*n*	Unsigned integer type of size *n* bits (n=8,16,32,64)
FMSTR_TSA_SINT*n*	Signed integer type of size *n* bits (n=8,16,32,64)
FMSTR_TSA_FRAC*n*	Fractional number of size *n* bits (n=16,32,64).
FMSTR_TSA_FRAC_Q(*m,n*)	Signed fractional number in general Q form (m+n+1 total bits)
FMSTR_TSA_FRAC_UQ(*m,n*)	Unsigned fractional number in general UQ form (m+n total bits)
FMSTR_TSA_FLOAT	4-byte standard IEEE floating-point type
FMSTR_TSA_DOUBLE	8-byte standard IEEE floating-point type
FMSTR_TSA_POINTER	Generic pointer type defined (platform-specific 16 or 32 bit)
FMSTR_TSA_USERTYPE(*name*)	Structure or union type declared with FMSTR_TSA_STRUCT record

TSA table list

There shall be exactly one TSA Table List in the application. The list contains one entry for each TSA table defined anywhere in the application.

The TSA Table List begins with the FMSTR_TSA_TABLE_LIST_BEGIN macro and continues with the TSA table entries for each table.

```
FMSTR_TSA_TABLE_LIST_BEGIN()

FMSTR_TSA_TABLE(table_id)
FMSTR_TSA_TABLE(table_id2)
FMSTR_TSA_TABLE(table_id3)
...
```

The list is closed with the FMSTR_TSA_TABLE_LIST_END macro:

```
FMSTR_TSA_TABLE_LIST_END()
```

TSA Active Content entries

FreeMASTER v2.0 and higher supports TSA Active Content, enabling the TSA tables to describe the memory-mapped files, virtual directories, and URL hyperlinks. FreeMASTER can access such objects similarly to accessing the files and folders on the local hard drive.

With this set of TSA entries, the FreeMASTER pages can be embedded directly into the target MCU flash and accessed by FreeMASTER directly over the communication line. The HTML-coded pages rendered inside the FreeMASTER window can access the TSA Active Content resources using a special URL referencing the *fmstr:* protocol.

This example provides an overview of the supported TSA Active Content entries:

```
FMSTR_TSA_TABLE_BEGIN(files_and_links)

/* Directory entry applies to all subsequent MEMFILE entries */
FMSTR_TSA_DIRECTORY("/text_files")     /* entering a new virtual directory */

/* The readme.txt file will be accessible at the fmstr://text_files/readme.txt URL */
FMSTR_TSA_MEMFILE("readme.txt", readme_txt, sizeof(readme_txt)) /* memory-mapped file */

/* Files can also be specified with a full path so the DIRECTORY entry does not apply */
FMSTR_TSA_MEMFILE("/index.htm", index, sizeof(index))          /* memory-mapped file */
FMSTR_TSA_MEMFILE("/prj/demo.pmp", demo_pmp, sizeof(demo_pmp)) /* memory-mapped file */

/* Hyperlinks can point to a local MEMFILE object or to the Internet */
FMSTR_TSA_HREF("Board's Built-in Welcome Page", "/index.htm")
FMSTR_TSA_HREF("FreeMASTER Home Page", "http://www.nxp.com/freemaster")

/* Project file links simplify opening the projects from any URLs */
FMSTR_TSA_PROJECT("Demonstration Project (embedded)", "/prj/demo.pmp")
FMSTR_TSA_PROJECT("Full Project (online)", "http://mycompany.com/prj/demo.pmp")

FMSTR_TSA_TABLE_END()
```

TSA API FMSTR_SetUpTsaBuff

Prototype

```
FMSTR_BOOL FMSTR_SetUpTsaBuff(FMSTR_ADDR buffAddr, FMSTR_SIZE buffSize);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_tsa.c*

Arguments

- *buffAddr* [in] - address of the memory buffer for the dynamic TSA table

- *buffSize* [in] - size of the memory buffer which determines the maximum number of TSA entries to be added in the runtime

Description

This function must be used to assign the RAM memory buffer to the TSA subsystem when FMSTR_USE_TSA_DYNAMIC is enabled. The memory buffer is then used to store the TSA entries added dynamically to the runtime TSA table using the FMSTR_TsaAddVar function call. The runtime TSA table is processed by the FreeMASTER PC Host tool along with all static tables as soon as the communication port is open.

The size of the memory buffer determines the number of TSA entries that can be added dynamically. Depending on the MCU platform, one TSA entry takes either 8 or 16 bytes.

FMSTR_TsaAddVar

Prototype

```
FMSTR_BOOL FMSTR_TsaAddVar(FMSTR_TSATBL_STRPTR tsaName, FMSTR_TSATBL_STRPTR
↪tsaType,
    FMSTR_TSATBL_VOIDPTR varAddr, FMSTR_SIZE32 varSize,
    FMSTR_SIZE flags);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_tsa.c*

Arguments

- *tsaName* [in] - name of the object
- *tsaType* [in] - name of the object type
- *varAddr* [in] - address of the object
- *varSize* [in] - size of the object
- *flags* [in] - access flags; a combination of these values:
  - *FMSTR_TSA_INFO_RO_VAR* — read-only memory-mapped object (typically a variable)
  - *FMSTR_TSA_INFO_RW_VAR* — read/write memory-mapped object
  - *FMSTR_TSA_INFO_NON_VAR* — other entry, describing structure types, structure members, enumerations, and other types

Description

This function can be called only when the dynamic TSA table is enabled by the FMSTR_USE_TSA_DYNAMIC configuration option and when the FMSTR_SetUpTsaBuff function call is made to assign the dynamic TSA table memory. This function adds an entry into the dynamic TSA table. It can be used to register a read-only or read/write memory object or describe an item of the user-defined type.

See *TSA table definition* for more details about the TSA table entries.

Application Commands API FMSTR_GetAppCmd

Prototype

```
FMSTR_APPCMD_CODE FMSTR_GetAppCmd(void);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_appcmd.c*

Description

This function can be used to detect if there is an Application Command waiting to be processed by the application. If no command is pending, this function returns the FMSTR_APPCMDRESULT_NOCMD constant. Otherwise, this function returns the code of the Application Command that must be processed. Use the FMSTR_AppCmdAck call to acknowledge the Application Command after it is processed and to return the appropriate result code to the host.

The FMSTR_GetAppCmd function does not report the commands for which a callback handler function exists. If 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.

FMSTR_GetAppCmdData

Prototype

```
FMSTR_APPCMD_PDATA FMSTR_GetAppCmdData(FMSTR_SIZE* dataLen);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_appcmd.c*

Arguments

- *dataLen* [out] - pointer to the variable that receives the length of the data available in the buffer. It can be NULL when this information is not needed.

Description

This function can be used to retrieve the Application Command data when the application determines that an Application Command is pending (see *FMSTR_GetAppCmd*).

There is just a single buffer to hold the Application Command data (the buffer length is FMSTR_APPCMD_BUFF_SIZE bytes). If the data are to be used in the application after the command is processed by the FMSTR_AppCmdAck call, copy the data out to a private buffer.

FMSTR_AppCmdAck

Prototype

```
void FMSTR_AppCmdAck(FMSTR_APPCMD_RESULT resultCode);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_appcmd.c*

Arguments

- *resultCode* [in] - the result code which is to be returned to FreeMASTER

Description

This function is used when the Application Command processing finishes in the application. The resultCode passed to this function is returned back to the host and the driver is re-initialized to expect the next Application Command.

After this function is called and before the next Application Command arrives, the return value of the FMSTR_GetAppCmd function is FMSTR_APPCMDRESULT_NOCMD.

FMSTR_AppCmdSetResponseData

Prototype

```
void FMSTR_AppCmdSetResponseData(FMSTR_ADDR resultDataAddr, FMSTR_SIZE resultDataLen);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_appcmd.c*

Arguments

- *resultDataAddr* [in] - pointer to the data buffer that is to be copied to the Application Command data buffer
- *resultDataLen* [in] - length of the data to be copied. It must not exceed the FMSTR_APPCMD_BUFF_SIZE value.

Description

This function can be used before the Application Command processing finishes, when there are data to be returned back to the PC.

The response data buffer is copied into the Application Command data buffer, from where it is accessed when the host requires it. Do not use FMSTR_GetAppCmdData and the data buffer after FMSTR_AppCmdSetResponseData is called.

Note: The current version of FreeMASTER does not support the Application Command response data.

FMSTR_RegisterAppCmdCall

Prototype

```
FMSTR_BOOL FMSTR_RegisterAppCmdCall(FMSTR_APPCMD_CODE appCmdCode, FMSTR_
↪PAPPCMDFUNC callbackFunc);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_appcmd.c*

Arguments

- *appCmdCode* [in] - the Application Command code for which the callback is to be registered
- *callbackFunc* [in] - pointer to the callback function that is to be registered. Use NULL to unregister a callback registered previously with this Application Command.

Return value

This function returns a non-zero value when the callback function was successfully registered or unregistered. It can return zero when trying to register a callback function for more than FMSTR_MAX_APPCMD_CALLS different Application Commands.

Description

This function can be used to register the given function as a callback handler for the Application Command. The Application Command is identified using 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 is

```
FMSTR_APPCMD_RESULT HandlerFunction(FMSTR_APPCMD_CODE nAppcmd,
    FMSTR_APPCMD_PDATA pData, FMSTR_SIZE nDataLen);
```

Where:

- *nAppcmd* -Application Command code
- *pData* —points to the Application Command data received (if any)
- *nDataLen* —information about the Application Command data length

The return value of the callback function is used as the Application Command Result Code and returned to FreeMASTER.

Note: The FMSTR_MAX_APPCMD_CALLS configuration macro defines how many different Application Commands may be handled by a callback function. When FMSTR_MAX_APPCMD_CALLS is undefined or defined as zero, the FMSTR_RegisterAppCmdCall function always fails.

Pipes API FMSTR_PipeOpen

Prototype

```
FMSTR_HPIPE FMSTR_PipeOpen(FMSTR_PIPE_PORT pipePort, FMSTR_PPIPEFUNC pipeCallback,
↪
    FMSTR_ADDR pipeRxBuff, FMSTR_PIPE_SIZE pipeRxSize,
    FMSTR_ADDR pipeTxBuff, FMSTR_PIPE_SIZE pipeTxSize,
    FMSTR_U8 type, const FMSTR_CHAR *name);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_pipes.c*

Arguments

- *pipePort* [in] - port number that identifies the pipe for the client
- *pipeCallback* [in] - pointer to the callback function that is called whenever a pipe data status changes
- *pipeRxBuff* [in] - address of the receive memory buffer
- *pipeRxSize* [in] - size of the receive memory buffer
- *pipeTxBuff* [in] - address of the transmit memory buffer
- *pipeTxSize* [in] - size of the transmit memory buffer
- *type* [in] - a combination of FMSTR_PIPE_MODE_xxx and FMSTR_PIPE_SIZE_xxx constants describing primary pipe data format and usage. This type helps FreeMASTER decide how to access the pipe by default. Optional, use 0 when undetermined.
- *name* [in] - user name of the pipe port. This name is visible to the FreeMASTER user when creating the graphical pipe interface.

Description

This function initializes a new pipe and makes it ready to accept or send the data to the PC Host client. The receive memory buffer is used to store the received data before they are read out by the FMSTR_PipeRead call. When this buffer gets full, the PC Host client denies the data transmission into this pipe until there is enough free space again. The transmit memory buffer is used to store the data transmitted by the application to the PC Host client using the FMSTR_PipeWrite call. The transmit buffer can get full when the PC Host is disconnected or when it is slow in receiving and reading out the pipe data.

The function returns the pipe handle which must be stored and used in the subsequent calls to manage the pipe object.

The callback function (if specified) is called whenever new data are received through the pipe and available for reading. This callback is also called when the data waiting in the transmit buffer are successfully pushed to the PC Host and the transmit buffer free space increases. The prototype of the callback function provided by the user application must be as follows. The *PipeHandler* name is only a placeholder and must be defined by the application.

```
void PipeHandler(FMSTR_HPIPE pipeHandle);
```

FMSTR_PipeClose

Prototype

```
void FMSTR_PipeClose(FMSTR_HPIPE pipeHandle);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_pipes.c*

Arguments

- *pipeHandle* [in] - pipe handle returned from the FMSTR_PipeOpen function call

Description

This function de-initializes the pipe object. No data can be received or sent on the pipe after this call.

FMSTR_PipeWrite

Prototype

```
FMSTR_PIPE_SIZE FMSTR_PipeWrite(FMSTR_HPIPE pipeHandle, FMSTR_ADDR pipeData,
    FMSTR_PIPE_SIZE pipeDataLen, FMSTR_PIPE_SIZE writeGranularity);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_pipes.c*

Arguments

- *pipeHandle* [in] - pipe handle returned from the FMSTR_PipeOpen function call
- *pipeData* [in] - address of the data to be written
- *pipeDataLen* [in] - length of the data to be written
- *writeGranularity* [in] - size of the minimum unit of data which is to be written

Description

This function puts the user-specified data into the pipe's transmit memory buffer and schedules it for transmission. This function returns the number of bytes that were successfully written into the buffer. This number may be smaller than the number of the requested bytes if there is not enough free space in the transmit buffer.

The *writeGranularity* argument can be used to split the data into smaller chunks, each of the size given by the *writeGranularity* value. The FMSTR_PipeWrite function writes as many data chunks as possible into the transmit buffer and does not attempt to write an incomplete chunk. This feature can prove to be useful to avoid the intermediate caching when writing an array of integer values or other multi-byte data items. When making the nGranularity value equal to the nLength value, all data are considered as one chunk which is either written successfully as a whole or not at all. The nGranularity value of 0 or 1 disables the data-chunk approach.

FMSTR_PipeRead

Prototype

```
FMSTR_PIPE_SIZE FMSTR_PipeRead(FMSTR_HPIPE pipeHandle, FMSTR_ADDR pipeData,
    FMSTR_PIPE_SIZE pipeDataLen, FMSTR_PIPE_SIZE readGranularity);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_pipes.c*

Arguments

- *pipeHandle* [in] - pipe handle returned from the FMSTR_PipeOpen function call
- *pipeData* [in] - address of the data buffer to be filled with the received data
- *pipeDataLen* [in] - length of the data to be read
- *readGranularity* [in] - size of the minimum unit of data which is to be read

Description

This function copies the data received from the pipe from its receive buffer to the user buffer for further processing. The function returns the number of bytes that were successfully copied to the buffer. This number may be smaller than the number of the requested bytes if there is not enough data bytes available in the receive buffer.

The readGranularity argument can be used to copy the data in larger chunks in the same way as described in the FMSTR_PipeWrite function.

API data types This section describes the data types used in the FreeMASTER driver. The information provided here can be useful when modifying or porting the FreeMASTER Communication Driver to new NXP platforms.

Note: The licensing conditions prohibit use of FreeMASTER and the FreeMASTER Communication Driver with non-NXP MPU or MCU products.

Public common types

The table below describes the public data types used in the FreeMASTER driver API calls. The data types are declared in the *freemaster.h* header file.

Type name	Description
FMSTR_ADDR	Data type used to hold the memory address. On most platforms, this is normally a C-pointer, but it may also be a pure integer type.
For example, this type is defined as long integer on the 56F8xxx platform where the 24-bit addresses must be supported, but the C-pointer may be only 16 bits wide in some compiler configurations.	
FMSTR_SIZE	Data type used to hold the memory block size.
It is required that this type is unsigned and at least 16 bits wide integer.	
FMSTR_BOOL	Data type used as a general boolean type.
This type is used only in zero/non-zero conditions in the driver code.	
FMSTR_APPCM	Data type used to hold the Application Command code.
Generally, this is an unsigned 8-bit value.	
FMSTR_APPCM	Data type used to create the Application Command data buffer.
Generally, this is an unsigned 8-bit value.	
FMSTR_APPCM	Data type used to hold the Application Command result code.
Generally, this is an unsigned 8-bit value.	

Public TSA types

The table describes the TSA-specific public data types. These types are declared in the *freemaster_tsa.h* header file, which is included in the user application indirectly by the *freemaster.h* file.

FMSTR_TSA_TII	Data type used to hold a descriptor index in the TSA table or a table index in the list of TSA tables.
By default, this is defined as FMSTR_SIZE.	
FMSTR_TSA_TS	Data type used to hold a memory block size, as used in the TSA descriptors.
By default, this is defined as FMSTR_SIZE.	

Public Pipes types

The table describes the data types used by the FreeMASTER Pipes API:

FMSTR_HPIPE	Pipe handle that identifies the open-pipe object.
Generally, this is a pointer to a void type.	
FMSTR_PIPE_P(	Integer type required to hold at least 7 bits of data.
Generally, this is an unsigned 8-bit or 16-bit type.	
FMSTR_PIPE_SI	Integer type required to hold at least 16 bits of data.
This is used to store the data buffer sizes.	
FMSTR_PPIPEF	Pointer to the pipe handler function.
See *FMSTR_PipeOpen* for more details.	

Internal types

The table describes the data types used internally by the FreeMASTER driver. The data types are declared in the platform-specific header file and they are not available in the application code.

FMSTR_U8	The smallest memory entity. On the vast majority of platforms, this is an unsigned 8-bit integer. On the 56F8xx DSP platform, this is defined as an unsigned 16-bit integer.
FMSTR_U16	Unsigned 16-bit integer.
FMSTR_U32	Unsigned 32-bit integer.
FMSTR_S8	Signed 8-bit integer.
FMSTR_S16	Signed 16-bit integer.
FMSTR_S32	Signed 32-bit integer.
FMSTR_FLOAT	4-byte standard IEEE floating-point type.
FMSTR_FLAGS	Data type forming a union with a structure of flag bit-fields.
FMSTR_SIZE8	Data type holding a general size value, at least 8 bits wide.
FMSTR_INDEX	General for-loop index. Must be signed, at least 16 bits wide.
FMSTR_BCHR	A single character in the communication buffer. Typically, this is an 8-bit unsigned integer, except for the DSP platforms where it is a 16-bit integer.
FMSTR_BPTR	A pointer to the communication buffer (an array of FMSTR_BCHR).

Document references

Links

- This document online: https://mcuxpresso.nxp.com/mcuxsdk/latest/html/middleware/freemaster/doc/index.html

- FreeMASTER tool home: www.nxp.com/freemaster
- FreeMASTER community area: community.nxp.com/community/freemaster
- FreeMASTER GitHub code repo: https://github.com/nxp-mcuxpresso/mcux-freemaster
- MCUXpresso SDK home: www.nxp.com/mcuxpresso
- MCUXpresso SDK builder: mcuxpresso.nxp.com/en

Documents

- *FreeMASTER Usage Serial Driver Implementation* (document AN4752)
- *Integrating FreeMASTER Time Debugging Tool With CodeWarrior For Microcontrollers v10.X Project* (document AN4771)
- *Flash Driver Library For MC56F847xx And MC56F827xx DSC Family* (document AN4860)

Revision history This Table summarizes the changes done to this document since the initial release.

Revision	Date	Description
1.0	03/2006	Limited initial release
2.0	09/2007	Updated for FreeMASTER version. New Freescale document template used.
2.1	12/2007	Added description of the new Fast Recorder feature and its API.
2.2	04/2010	Added support for MPC56xx platform, Added new API for use CAN interface.
2.3	04/2011	Added support for Kxx Kinetis platform and MQX operating system.
2.4	06/2011	Serial driver update, adds support for USB CDC interface.
2.5	08/2011	Added Packet Driven BDM interface.
2.7	12/2013	Added FLEXCAN32 interface, byte access and isr callback configuration option.
2.8	06/2014	Removed obsolete license text, see the software package content for up-to-date license.
2.9	03/2015	Update for driver version 1.8.2 and 1.9: FreeMASTER Pipes, TSA Active Content, LIN Transport Layer support, DEBUG-TX communication troubleshooting, Kinetis SDK support.
3.0	08/2016	Update for driver version 2.0: Added support for MPC56xx, MPC57xx, KEAxx and S32Kxx platforms. New NXP document template as well as new license agreement used. added MCAN interface. Folders structure at the installation destination was rearranged.
4.0	04/2019	Update for driver released as part of FreeMASTER v3.0 and MCUXpresso SDK 2.6. Updated to match new V4 serial communication protocol and new configuration options. This version of the document removes substantial portion of outdated information related to S08, S12, ColdFire, Power and other legacy platforms.
4.1	04/2020	Minor update for FreeMASTER driver included in MCUXpresso SDK 2.8.
4.2	09/2020	Added example applications description and information about the MCUXpresso Config Tools. Fixed the pipe-related API description.
4.3	10/2024	Added description of Network and Segger J-Link RTT interface configuration. Accompanying the MCUXpresso SDK version 24.12.00.
4.4	04/2025	Added Zephyr-specific information. Accompanying the MCUXpresso SDK version 25.06.00.

3.4 Multicore SDK

Multicore Software Development Kit (MCSDK) provides comprehensive software support for NXP multicore devices. The MCSDK is combined with the MCUXpresso SDK to form a framework for easy development of multicore applications.

3.4.1 Quick links

- *Release Notes*

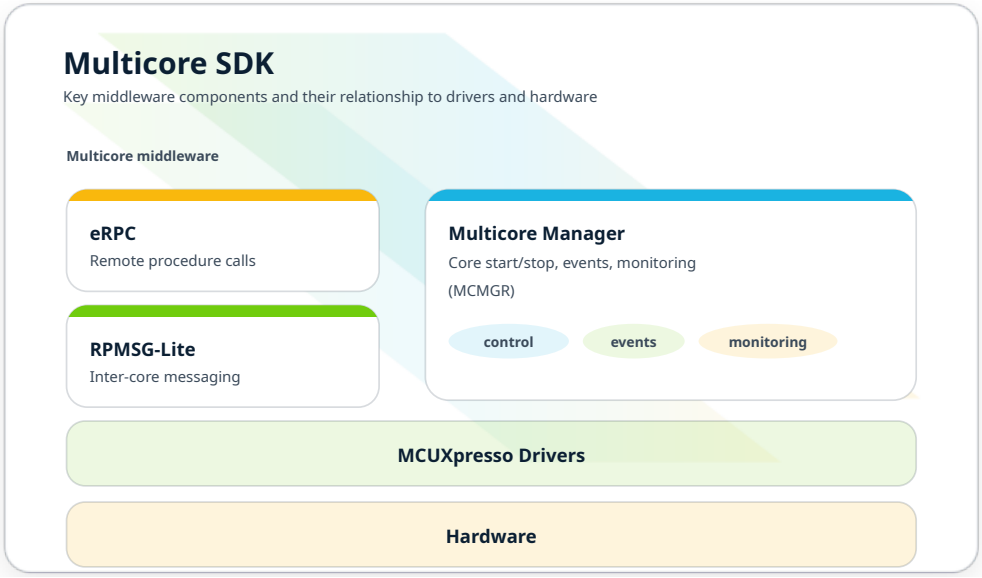


Fig. 1: Multicore SDK software stack (simplified).

- *Getting Started*
- Multicore SDK Changelog

3.4.2 Components

Component	Description
RPMSG-Lite	Lightweight implementation of the Remote Processor Messaging (RPMsg) protocol for inter-core messaging.
Multicore Manager	Services for multicore systems (core start/stop, events, and monitoring).
eRPC	Embedded RPC system suitable for multicore and multiprocessor designs.

MCSDK Release Notes

MCSDK Getting Started

RPMSG-Lite

Quick links

- Changelog
- API documentation (Doxygen): https://nxp-mcuxpresso.github.io/rpmsg-lite/

Multicore Manager (MCMGR)

Quick links

- Changelog
- API documentation (Doxygen): https://nxp-mcuxpresso.github.io/mcux-mcmgr/

eRPC

eRPC (Embedded RPC) is an open-source remote procedure call (RPC) system suitable for multi-core and multiprocessor embedded systems.

Quick links

- *Getting Started*
- Changelog
- Upstream project: https://github.com/EmbeddedRPC/erpc

eRPC Getting Started

Chapter 4

RTOS

4.1 FreeRTOS

4.1.1 FreeRTOS kernel

Open source RTOS kernel for small devices.

FreeRTOS kernel for MCUXpresso SDK Readme

MCUXpresso SDK: FreeRTOS Kernel NXP Integration This repository is the NXP integration layer for the FreeRTOS kernel (https://github.com/FreeRTOS/FreeRTOS-Kernel). It allows original FreeRTOS kernel upstream sources build in MCUXpresso SDK. It is part of the MCUXpresso SDK overall delivery which is composed of several sub-repositories/projects. Navigate to the top/parent repository mcuxsdk-manifests(https://github.com/nxp-mcuxpresso/mcuxsdk-manifests) for the complete delivery of MCUXpresso SDK.

For more information about the FreeRTOS kernel repo adoption see README_mcuxsdk.md: FreeRTOS kernel for MCUXpresso SDK Readme document.

FreeRTOS kernel for MCUXpresso SDK Overview

The purpose of this document is to describes the FreeRTOS kernel repo integration into the NXP MCUXpresso Software Development Kit: mcuxsdk. MCUXpresso SDK provides a comprehensive development solutions designed to optimize, ease, and help accelerate embedded system development of applications based on MCUs from NXP. This project involves the FreeRTOS kernel repo fork with:

- cmake and Kconfig support to allow the configuration and build in MCUXpresso SDK ecosystem
- FreeRTOS OS additions, such as FreeRTOS driver wrappers, RTOS ready FatFs file system, and the implementation of FreeRTOS tickless mode

The history of changes in FreeRTOS kernel repo for MCUXpresso SDK are summarized in *CHANGELOG.md* file.

The MCUXpresso SDK framework also contains a set of FreeRTOS examples which show basic FreeRTOS OS features. This makes it easy to start a new FreeRTOS project or begin experimenting with FreeRTOS OS. Selected drivers and middleware are RTOS ready with related FreeRTOS adaptation layer.

FreeRTOS example applications

The FreeRTOS examples are written to demonstrate basic FreeRTOS features and the interaction between peripheral drivers and the RTOS.

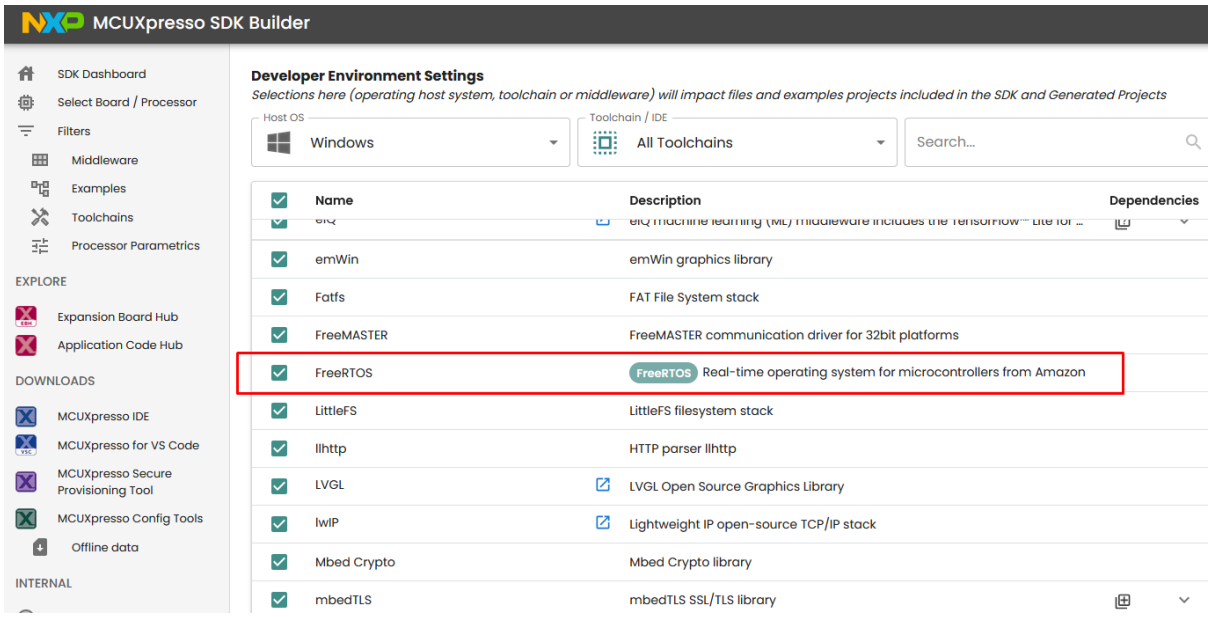
List of examples

The list of freertos_examples, their description and availability for individual supported MCUXpresso SDK development boards can be obtained here: https://mcuxpresso.nxp.com/mcuxsdk/latest/html/examples/freertos_examples/index.html

Location of examples

The FreeRTOS examples are located in mcuxsdk-examples repository, see the freertos_examples folder.

Once using MCUXpresso SDK zip packages created via the MCUXpresso SDK Builder the FreeRTOS kernel library and associated freertos_examples are added into final zip package once FreeRTOS components is selected on the Developer Environment Settings page:



The FreeRTOS examples in MCUXpresso SDK zip packages are located in <MCUXpressoSDK_install_dir>/boards/<board_name>/freertos_examples/ subfolders.

Building a FreeRTOS example application

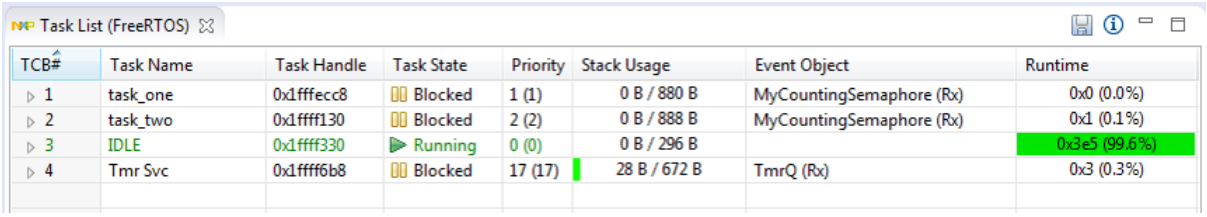
For information how to use the cmake and Kconfig based build and configuration system and how to build freertos_examples visit: MCUXpresso SDK documentation for Build And Configuration MCUXpresso SDK Getting Start Guide

Tip: To list all FreeRTOS example projects and targets that can be built via the west build command, use this west list_project command in mcuxsdk workspace:

```
west list_project -p examples/freertos_examples
```

FreeRTOS aware debugger plugin

NXP provides FreeRTOS task aware debugger for GDB. The plugin is compatible with Eclipse-based (MCUXpressoIDE) and is available after the installation.



TCB#	Task Name	Task Handle	Task State	Priority	Stack Usage	Event Object	Runtime
1	task_one	0x1fffecc8	Blocked	1 (1)	0 B / 880 B	MyCountingSemaphore (Rx)	0x0 (0.0%)
2	task_two	0x1ffff130	Blocked	2 (2)	0 B / 888 B	MyCountingSemaphore (Rx)	0x1 (0.1%)
3	IDLE	0x1ffff330	Running	0 (0)	0 B / 296 B		0x3e5 (99.6%)
4	Tmr Svc	0x1ffff6b8	Blocked	17 (17)	28 B / 672 B	TmrQ (Rx)	0x3 (0.3%)

FreeRTOS kernel for MCUXpresso SDK ChangeLog

Changelog FreeRTOS kernel for MCUXpresso SDK All notable changes to this project will be documented in this file.

The format is based on Keep a Changelog, and this project adheres to Semantic Versioning.

[Unreleased]

Fixed

- Temporary workaround for FreeRTOS-Kernel upstream bug #1480: stray URL (http://files.iar.com/ftp/pub/box/bxarm-9.60.3.deb) accidentally placed outside /* */ comment delimiters on line 466 of the IAR CM33/CM55/CM85 TrustZone non-secure portasm.s files (introduced in upstream commit 78e0cc778a, PR #1195). Fixed copies are placed under portable/IAR/ARM_CM{33,55,85}/non_secure/portasm.s and the CMakeLists.txt SOURCES entries for the cm33/cm55/cm85_trustzone.non_secure IAR toolchain blocks are redirected to those copies. Revert the three CMakeLists.txt lines once the upstream fix is merged and the freertos-kernel-upstream revision is bumped past it, then delete portable/IAR/ARM_CM{33,55,85}/ from this repo.

Added

[11.2.0_rev0]

- update amazon freertos version

[11.1.0_rev0]

- update amazon freertos version

[11.0.1_rev0]

- update amazon freertos version

[10.5.1_rev0]

- update amazon freertos version

[10.4.3_rev1]

- Apply CM33 security fix from 10.4.3-LTS-Patch-2. See rtos\freertos\freertos_kernel\History.txt
- Apply CM33 security fix from 10.4.3-LTS-Patch-1. See rtos\freertos\freertos_kernel\History.txt

[10.4.3_rev0]

- update amazon freertos version.

[10.4.3_rev0]

- update amazon freertos version.

[9.0.0_rev3]

- New features:
  - Tickless idle mode support for Cortex-A7. Add fsl_tickless_epit.c and fsl_tickless_generic.h in portable/IAR/ARM_CA9 folder.
  - Enabled float context saving in IAR for Cortex-A7. Added configUSE_TASK_FPU_SUPPORT macros. Modified port.c and portmacro.h in portable/IAR/ARM_CA9 folder.
- Other changes:
  - Transformed ARM_CM core specific tickless low power support into generic form under freertos/Source/portable/low_power_tickless/.

[9.0.0_rev2]

- New features:
  - Enabled MCUXpresso thread aware debugging. Add freertos_tasks_c_additions.h and configINCLUDE_FREERTOS_TASK_C_ADDITIONS_H and configFREERTOS_MEMORY_SCHEME macros.

[9.0.0_rev1]

- New features:
  - Enabled -flto optimization in GCC by adding **attribute**((used)) for vTaskSwitchContext.
  - Enabled KDS Task Aware Debugger. Apply FreeRTOS patch to enable configRECORD_STACK_HIGH_ADDRESS macro. Modified files are task.c and FreeRTOS.h.

[9.0.0_rev0]

- New features:
  - Example freertos_sem_static.
  - Static allocation support RTOS driver wrappers.
- Other changes:
  - Tickless idle rework. Support for different timers is in separated files (fsl_tickless_systick.c, fsl_tickless_lptmr.c).
  - Removed configuration option configSYSTICK_USE_LOW_POWER_TIMER. Low power timer is now selected by linking of apropriate file fsl_tickless_lptmr.c.
  - Removed configOVERRIDE_DEFAULT_TICK_CONFIGURATION in RVDS port. Use of **attribute**((weak)) is the preferred solution. Not same as _weak!

[8.2.3]

- New features:
  - Tickless idle mode support.
  - Added template application for Kinetis Expert (KEx) tool (template_application).
- Other changes:
  - Folder structure reduction. Keep only Kinetis related parts.

FreeRTOS kernel Readme

4.1.2 FreeRTOS drivers

This is set of NXP provided FreeRTOS reentrant bus drivers.

4.1.3 backoffalgorithm

Algorithm for calculating exponential backoff with jitter for network retry attempts.

Readme

MCUXpresso SDK: backoffAlgorithm Library NXP Integration This repository is the NXP integration layer for the backoffAlgorithm library (https://github.com/FreeRTOS/backoffalgorithm). It allows original backoffAlgorithm upstream sources build in MCUXpresso SDK. It is part of the MCUXpresso SDK overall delivery which is composed of several sub-repositories/projects. Navigate to the top/parent repository mcuxsdk-manifests(https://github.com/nxp-mcuxpresso/mcuxsdk-manifests) for the complete delivery of MCUXpresso SDK.

4.1.4 corehttp

C language HTTP client library designed for embedded platforms.

MCUXpresso SDK: coreHTTP Client Library NXP Integration

This repository is the NXP integration layer for the coreHTTP Client library (https://github.com/FreeRTOS/corehttp). It allows original coreHTTP Client upstream sources build in MCUXpresso SDK. It is part of the MCUXpresso SDK overall delivery which is composed of several sub-repositories/projects. Navigate to the top/parent repository mcuxsdk-manifests(https://github.com/nxp-mcuxpresso/mcuxsdk-manifests) for the complete delivery of MCUXpresso SDK.

4.1.5 corejson

JSON parser.

Readme

MCUXpresso SDK: coreJSON Library NXP Integration This repository is the NXP integration layer for the coreJSON library (https://github.com/FreeRTOS/corejson). It allows original coreJSON upstream sources build in MCUXpresso SDK. It is part of the MCUXpresso SDK overall delivery which is composed of several sub-repositories/projects. Navigate to the top/parent repository mcuxsdk-manifests(https://github.com/nxp-mcuxpresso/mcuxsdk-manifests) for the complete delivery of MCUXpresso SDK.

4.1.6 coremqtt

MQTT publish/subscribe messaging library.

MCUXpresso SDK: coreMQTT Library NXP Integration

This repository is the NXP integration layer for the coreMQTT library (https://github.com/FreeRTOS/coremqtt). It allows original coreMQTT upstream sources build in MCUXpresso SDK. It is part of the MCUXpresso SDK overall delivery which is composed of several sub-repositories/projects. Navigate to the top/parent repository mcuxsdk-manifests(https://github.com/nxp-mcuxpresso/mcuxsdk-manifests) for the complete delivery of MCUXpresso SDK.

4.1.7 corepkcs11

PKCS #11 key management library.

Readme

MCUXpresso SDK: corePKCS11 Library NXP Integration This repository is the NXP integration layer for the PKCS #11 key management library (https://github.com/FreeRTOS/corePKCS11). It allows original PKCS #11 key management upstream sources build in MCUXpresso SDK. It is part of the MCUXpresso SDK overall delivery which is composed of several sub-repositories/projects. Navigate to the top/parent repository mcuxsdk-manifests(https://github.com/nxp-mcuxpresso/mcuxsdk-manifests) for the complete delivery of MCUXpresso SDK.

4.1.8 freertos-plus-tcp

Open source RTOS FreeRTOS Plus TCP.

Readme

MCUXpresso SDK: FreeRTOS-Plus-TCP Library NXP Integration This repository is the NXP integration layer for the FreeRTOS-Plus-TCP library (https://github.com/FreeRTOS/freertos-plus-tcp). It allows original FreeRTOS-Plus-TCP upstream sources build in MCUXpresso SDK. It is part of the MCUXpresso SDK overall delivery which is composed of several sub-repositories/projects. Navigate to the top/parent repository mcuxsdk-manifests(https://github.com/nxp-mcuxpresso/mcuxsdk-manifests) for the complete delivery of MCUXpresso SDK.

Chapter 5

Downloads

This page is generated automatically by the “downloads_index“ Sphinx extension.
4 downloadable file(s) referenced across 3 page(s), grouped into 2 categories:

5.1 boards

- mcuxsdk-frdmmcxa366.pdf — from *boards/MCX/frdmmcxa366/index*

5.2 develop

- evkbmimxrt1170_custom (.zip) — from develop/sdk/custom_board_development
- frdmmcxa346_custom (.zip) — from develop/sdk/custom_board_development
- example (.zip) — from develop/sdk/integration

Index

D

drivers_MCX_MCXA_MCXA366.___cdog_debug_Action_ctrl_enum (*C enum*), 208
drivers_MCX_MCXA_MCXA366.___cdog_debug_Action_ctrl_enum.kCDOG_DebugHaltCtrl_Pause (*C enumerator*), 208
drivers_MCX_MCXA_MCXA366.___cdog_debug_Action_ctrl_enum.kCDOG_DebugHaltCtrl_Run (*C enumerator*), 208
drivers_MCX_MCXA_MCXA366.___cdog_fault_ctrl_enum (*C enum*), 208
drivers_MCX_MCXA_MCXA366.___cdog_fault_ctrl_enum.kCDOG_FaultCtrl_EnableInterrupt (*C enumerator*), 208
drivers_MCX_MCXA_MCXA366.___cdog_fault_ctrl_enum.kCDOG_FaultCtrl_EnableReset (*C enumerator*), 208
drivers_MCX_MCXA_MCXA366.___cdog_fault_ctrl_enum.kCDOG_FaultCtrl_NoAction (*C enumerator*), 208
drivers_MCX_MCXA_MCXA366.___cdog_irq_pause_ctrl_enum (*C enum*), 208
drivers_MCX_MCXA_MCXA366.___cdog_irq_pause_ctrl_enum.kCDOG_IrqPauseCtrl_Pause (*C enumerator*), 208
drivers_MCX_MCXA_MCXA366.___cdog_irq_pause_ctrl_enum.kCDOG_IrqPauseCtrl_Run (*C enumerator*), 208
drivers_MCX_MCXA_MCXA366.___code_lock_ctrl_enum (*C enum*), 208
drivers_MCX_MCXA_MCXA366.___code_lock_ctrl_enum.kCDOG_LockCtrl_Lock (*C enumerator*), 209
drivers_MCX_MCXA_MCXA366.___code_lock_ctrl_enum.kCDOG_LockCtrl_Unlock (*C enumerator*), 209
drivers_MCX_MCXA_MCXA366._aoi_event (*C enum*), 202
drivers_MCX_MCXA_MCXA366._aoi_event_config (*C struct*), 203
drivers_MCX_MCXA_MCXA366._aoi_event_config.PT0AC (*C var*), 203
drivers_MCX_MCXA_MCXA366._aoi_event_config.PT0BC (*C var*), 203
drivers_MCX_MCXA_MCXA366._aoi_event_config.PT0CC (*C var*), 203
drivers_MCX_MCXA_MCXA366._aoi_event_config.PT0DC (*C var*), 204
drivers_MCX_MCXA_MCXA366._aoi_event_config.PT1AC (*C var*), 204
drivers_MCX_MCXA_MCXA366._aoi_event_config.PT1BC (*C var*), 204
drivers_MCX_MCXA_MCXA366._aoi_event_config.PT1CC (*C var*), 204
drivers_MCX_MCXA_MCXA366._aoi_event_config.PT1DC (*C var*), 204
drivers_MCX_MCXA_MCXA366._aoi_event_config.PT2AC (*C var*), 204
drivers_MCX_MCXA_MCXA366._aoi_event_config.PT2BC (*C var*), 204
drivers_MCX_MCXA_MCXA366._aoi_event_config.PT2CC (*C var*), 204
drivers_MCX_MCXA_MCXA366._aoi_event_config.PT2DC (*C var*), 204
drivers_MCX_MCXA_MCXA366._aoi_event_config.PT3AC (*C var*), 204
drivers_MCX_MCXA_MCXA366._aoi_event_config.PT3BC (*C var*), 204
drivers_MCX_MCXA_MCXA366._aoi_event_config.PT3CC (*C var*), 204
drivers_MCX_MCXA_MCXA366._aoi_event_config.PT3DC (*C var*), 204
drivers_MCX_MCXA_MCXA366._aoi_event.kAOI_Event0 (*C enumerator*), 203
drivers_MCX_MCXA_MCXA366._aoi_event.kAOI_Event1 (*C enumerator*), 203
drivers_MCX_MCXA_MCXA366._aoi_event.kAOI_Event2 (*C enumerator*), 203
drivers_MCX_MCXA_MCXA366._aoi_event.kAOI_Event3 (*C enumerator*), 203
drivers_MCX_MCXA_MCXA366._aoi_input_config (*C enum*), 202

drivers_MCX_MCXA_MCXA366._aoi_input_config.kAOI_InputSignal (*C enumerator*), 202
drivers_MCX_MCXA_MCXA366._aoi_input_config.kAOI_InvInputSignal (*C enumerator*), 202
drivers_MCX_MCXA_MCXA366._aoi_input_config.kAOI_LogicOne (*C enumerator*), 202
drivers_MCX_MCXA_MCXA366._aoi_input_config.kAOI_LogicZero (*C enumerator*), 202
drivers_MCX_MCXA_MCXA366._cmc_clock_mode (*C enum*), 773
drivers_MCX_MCXA_MCXA366._cmc_clock_mode.kCMC_GateAllSystemClocks (*C enumerator*), 773
drivers_MCX_MCXA_MCXA366._cmc_clock_mode.kCMC_GateAllSystemClocksEnterLowPowerMode (*C enumerator*), 773
drivers_MCX_MCXA_MCXA366._cmc_clock_mode.kCMC_GateCoreClock (*C enumerator*), 773
drivers_MCX_MCXA_MCXA366._cmc_clock_mode.kCMC_GateCorePlatformClock (*C enumerator*), 773
drivers_MCX_MCXA_MCXA366._cmc_clock_mode.kCMC_GateNoneClock (*C enumerator*), 773
drivers_MCX_MCXA_MCXA366._cmc_core_clock_gate_status (*C enum*), 773
drivers_MCX_MCXA_MCXA366._cmc_core_clock_gate_status.kCMC_CoreClockGated (*C enumerator*), 773
drivers_MCX_MCXA_MCXA366._cmc_core_clock_gate_status.kCMC_CoreClockNotGated (*C enumerator*), 773
drivers_MCX_MCXA_MCXA366._cmc_low_power_mode (*C enum*), 773
drivers_MCX_MCXA_MCXA366._cmc_low_power_mode.kCMC_ActiveOrSleepMode (*C enumerator*), 773
drivers_MCX_MCXA_MCXA366._cmc_low_power_mode.kCMC_DeepPowerDown (*C enumerator*), 773
drivers_MCX_MCXA_MCXA366._cmc_low_power_mode.kCMC_DeepSleepMode (*C enumerator*), 773
drivers_MCX_MCXA_MCXA366._cmc_low_power_mode.kCMC_PowerDownMode (*C enumerator*), 773
drivers_MCX_MCXA_MCXA366._cmc_power_domain_config (*C struct*), 782
drivers_MCX_MCXA_MCXA366._cmc_power_mode_protection (*C enum*), 769
drivers_MCX_MCXA_MCXA366._cmc_power_mode_protection.kCMC_AllowAllLowPowerModes (*C enumerator*), 769
drivers_MCX_MCXA_MCXA366._cmc_power_mode_protection.kCMC_AllowDeepPowerDownMode (*C enumerator*), 769
drivers_MCX_MCXA_MCXA366._cmc_power_mode_protection.kCMC_AllowDeepSleepMode (*C enumerator*), 769
drivers_MCX_MCXA_MCXA366._cmc_power_mode_protection.kCMC_AllowPowerDownMode (*C enumerator*), 769
drivers_MCX_MCXA_MCXA366._cmc_reset_pin_config (*C struct*), 782
drivers_MCX_MCXA_MCXA366._cmc_system_reset_interrupt_enable (*C enum*), 770
drivers_MCX_MCXA_MCXA366._cmc_system_reset_interrupt_enable.kCMC_DAPResetInterruptEnable (*C enumerator*), 770
drivers_MCX_MCXA_MCXA366._cmc_system_reset_interrupt_enable.kCMC_LockupResetInterruptEnable (*C enumerator*), 770
drivers_MCX_MCXA_MCXA366._cmc_system_reset_interrupt_enable.kCMC_LowPowerAcknowledgeTimeoutRese (*C enumerator*), 770
drivers_MCX_MCXA_MCXA366._cmc_system_reset_interrupt_enable.kCMC_PinResetInterruptEnable (*C enumerator*), 770
drivers_MCX_MCXA_MCXA366._cmc_system_reset_interrupt_enable.kCMC_SoftwareResetInterruptEnable (*C enumerator*), 770
drivers_MCX_MCXA_MCXA366._cmc_system_reset_interrupt_flag (*C enum*), 770
drivers_MCX_MCXA_MCXA366._cmc_system_reset_interrupt_flag.kCMC_DAPResetInterruptFlag (*C enumerator*), 770
drivers_MCX_MCXA_MCXA366._cmc_system_reset_interrupt_flag.kCMC_LockupResetInterruptFlag (*C enumerator*), 770
drivers_MCX_MCXA_MCXA366._cmc_system_reset_interrupt_flag.kCMC_LowPowerAcknowledgeTimeoutResetF (*C enumerator*), 770
drivers_MCX_MCXA_MCXA366._cmc_system_reset_interrupt_flag.kCMC_PinResetInterruptFlag (*C enumerator*), 770

drivers_MCX_MCXA_MCXA366._cmc_system_reset_interrupt_flag.kCMC_SoftwareResetInterruptFlag (*C enumerator*), 770
drivers_MCX_MCXA_MCXA366._cmc_system_reset_sources (*C enum*), 772
drivers_MCX_MCXA_MCXA366._cmc_system_reset_sources.kCMC_DAPReset (*C enumerator*), 772
drivers_MCX_MCXA_MCXA366._cmc_system_reset_sources.kCMC_FatalReset (*C enumerator*), 772
drivers_MCX_MCXA_MCXA366._cmc_system_reset_sources.kCMC_JTAGSystemReset (*C enumerator*), 773
drivers_MCX_MCXA_MCXA366._cmc_system_reset_sources.kCMC_LockUoReset (*C enumerator*), 772
drivers_MCX_MCXA_MCXA366._cmc_system_reset_sources.kCMC_LowPowerAcknowledgeTimeoutReset (*C enumerator*), 772
drivers_MCX_MCXA_MCXA366._cmc_system_reset_sources.kCMC_PinReset (*C enumerator*), 772
drivers_MCX_MCXA_MCXA366._cmc_system_reset_sources.kCMC_PORReset (*C enumerator*), 772
drivers_MCX_MCXA_MCXA366._cmc_system_reset_sources.kCMC_ResetTimeout (*C enumerator*), 772
drivers_MCX_MCXA_MCXA366._cmc_system_reset_sources.kCMC_SCGReset (*C enumerator*), 772
drivers_MCX_MCXA_MCXA366._cmc_system_reset_sources.kCMC_SoftwareReset (*C enumerator*), 772
drivers_MCX_MCXA_MCXA366._cmc_system_reset_sources.kCMC_WakeUpReset (*C enumerator*), 772
drivers_MCX_MCXA_MCXA366._cmc_system_reset_sources.kCMC_WarmReset (*C enumerator*), 772
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays (*C enum*), 770
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_AllSramArrays (*C enumerator*), 772
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_CAN0_CAN1_ENET_USB1 (*C enumerator*), 772
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_DMA0_DMA1_PKC (*C enumerator*), 771
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_FlexSPI (*C enumerator*), 772
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_LPCAC (*C enumerator*), 771
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_PQ (*C enumerator*), 772
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_RAMB (*C enumerator*), 771
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_RAMC0 (*C enumerator*), 771
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_RAMC1 (*C enumerator*), 771
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_RAMD0 (*C enumerator*), 771
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_RAMD1 (*C enumerator*), 771
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_RAME0 (*C enumerator*), 771
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_RAME1 (*C enumerator*), 771
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_RAMF0 (*C enumerator*), 771
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_RAMF1 (*C enumerator*), 771
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_RAMG0_RAMG1 (*C enumerator*), 771
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_RAMG2_RAMG3 (*C enumerator*), 771
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_RAMH0_RAMH1 (*C enumerator*), 771
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_RAMX0 (*C enumerator*), 770
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_RAMX1 (*C enumerator*), 770
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_RAMX2 (*C enumerator*), 771
drivers_MCX_MCXA_MCXA366._cmc_system_sram_arrays.kCMC_USB0 (*C enumerator*), 771
drivers_MCX_MCXA_MCXA366._cmc_wakeup_sources (*C enum*), 769
drivers_MCX_MCXA_MCXA366._cmc_wakeup_sources.kCMC_WakeupFromCpu1 (*C enumera-*

tor), 769
drivers_MCX_MCXA_MCXA366._cmc_wakeup_sources.kCMC_WakeupFromDebugReuqest (*C enumerator*), 769
drivers_MCX_MCXA_MCXA366._cmc_wakeup_sources.kCMC_WakeupFromDMAWakeup (*C enumerator*), 769
drivers_MCX_MCXA_MCXA366._cmc_wakeup_sources.kCMC_WakeupFromInterrupt (*C enumerator*), 769
drivers_MCX_MCXA_MCXA366._cmc_wakeup_sources.kCMC_WakeupFromITRC (*C enumerator*), 769
drivers_MCX_MCXA_MCXA366._cmc_wakeup_sources.kCMC_WakeupFromResetInterruptOrPowerDown (*C enumerator*), 769
drivers_MCX_MCXA_MCXA366._cmc_wakeup_sources.kCMC_WakeupFromUsbFs (*C enumerator*), 769
drivers_MCX_MCXA_MCXA366._cmc_wakeup_sources.kCMC_WakeupFromWUURequest (*C enumerator*), 769
drivers_MCX_MCXA_MCXA366._crc_bits (*C enum*), 210
drivers_MCX_MCXA_MCXA366._crc_bits.kCrcBits16 (*C enumerator*), 210
drivers_MCX_MCXA_MCXA366._crc_bits.kCrcBits32 (*C enumerator*), 210
drivers_MCX_MCXA_MCXA366._crc_config (*C struct*), 212
drivers_MCX_MCXA_MCXA366._crc_config.complementChecksum (*C var*), 212
drivers_MCX_MCXA_MCXA366._crc_config.crcBits (*C var*), 212
drivers_MCX_MCXA_MCXA366._crc_config.crcResult (*C var*), 212
drivers_MCX_MCXA_MCXA366._crc_config.polynomial (*C var*), 212
drivers_MCX_MCXA_MCXA366._crc_config.reflectIn (*C var*), 212
drivers_MCX_MCXA_MCXA366._crc_config.reflectOut (*C var*), 212
drivers_MCX_MCXA_MCXA366._crc_config.seed (*C var*), 212
drivers_MCX_MCXA_MCXA366._crc_result (*C enum*), 210
drivers_MCX_MCXA_MCXA366._crc_result.kCrcFinalChecksum (*C enumerator*), 210
drivers_MCX_MCXA_MCXA366._crc_result.kCrcIntermediateChecksum (*C enumerator*), 210
drivers_MCX_MCXA_MCXA366._ctimer_capture_channel (*C enum*), 215
drivers_MCX_MCXA_MCXA366._ctimer_capture_channel.kCTIMER_Capture_0 (*C enumerator*), 215
drivers_MCX_MCXA_MCXA366._ctimer_capture_channel.kCTIMER_Capture_1 (*C enumerator*), 215
drivers_MCX_MCXA_MCXA366._ctimer_capture_channel.kCTIMER_Capture_3 (*C enumerator*), 216
drivers_MCX_MCXA_MCXA366._ctimer_capture_edge (*C enum*), 216
drivers_MCX_MCXA_MCXA366._ctimer_capture_edge.kCTIMER_Capture_BothEdge (*C enumerator*), 216
drivers_MCX_MCXA_MCXA366._ctimer_capture_edge.kCTIMER_Capture_FallEdge (*C enumerator*), 216
drivers_MCX_MCXA_MCXA366._ctimer_capture_edge.kCTIMER_Capture_RiseEdge (*C enumerator*), 216
drivers_MCX_MCXA_MCXA366._ctimer_config (*C struct*), 222
drivers_MCX_MCXA_MCXA366._ctimer_config.input (*C var*), 222
drivers_MCX_MCXA_MCXA366._ctimer_config.mode (*C var*), 222
drivers_MCX_MCXA_MCXA366._ctimer_config.prescale (*C var*), 223
drivers_MCX_MCXA_MCXA366._ctimer_external_match (*C enum*), 216
drivers_MCX_MCXA_MCXA366._ctimer_external_match.kCTIMER_External_Match_0 (*C enumerator*), 216
drivers_MCX_MCXA_MCXA366._ctimer_external_match.kCTIMER_External_Match_1 (*C enumerator*), 216
drivers_MCX_MCXA_MCXA366._ctimer_external_match.kCTIMER_External_Match_2 (*C enumerator*), 216
drivers_MCX_MCXA_MCXA366._ctimer_external_match.kCTIMER_External_Match_3 (*C enumerator*), 216
drivers_MCX_MCXA_MCXA366._ctimer_interrupt_enable (*C enum*), 217
drivers_MCX_MCXA_MCXA366._ctimer_interrupt_enable.kCTIMER_Match0InterruptEnable (*C*

enumerator), 217
drivers_MCX_MCXA_MCXA366._ctimer_interrupt_enable.kCTIMER_Match1InterruptEnable (*C enumerator*), 217
drivers_MCX_MCXA_MCXA366._ctimer_interrupt_enable.kCTIMER_Match2InterruptEnable (*C enumerator*), 217
drivers_MCX_MCXA_MCXA366._ctimer_interrupt_enable.kCTIMER_Match3InterruptEnable (*C enumerator*), 217
drivers_MCX_MCXA_MCXA366._ctimer_match (*C enum*), 216
drivers_MCX_MCXA_MCXA366._ctimer_match_config (*C struct*), 222
drivers_MCX_MCXA_MCXA366._ctimer_match_config.enableCounterReset (*C var*), 222
drivers_MCX_MCXA_MCXA366._ctimer_match_config.enableCounterStop (*C var*), 222
drivers_MCX_MCXA_MCXA366._ctimer_match_config.enableInterrupt (*C var*), 222
drivers_MCX_MCXA_MCXA366._ctimer_match_config.matchValue (*C var*), 222
drivers_MCX_MCXA_MCXA366._ctimer_match_config.outControl (*C var*), 222
drivers_MCX_MCXA_MCXA366._ctimer_match_config.outPinInitState (*C var*), 222
drivers_MCX_MCXA_MCXA366._ctimer_match_output_control (*C enum*), 217
drivers_MCX_MCXA_MCXA366._ctimer_match_output_control.kCTIMER_Output_Clear (*C enumerator*), 217
drivers_MCX_MCXA_MCXA366._ctimer_match_output_control.kCTIMER_Output_NoAction (*C enumerator*), 217
drivers_MCX_MCXA_MCXA366._ctimer_match_output_control.kCTIMER_Output_Set (*C enumerator*), 217
drivers_MCX_MCXA_MCXA366._ctimer_match_output_control.kCTIMER_Output_Toggle (*C enumerator*), 217
drivers_MCX_MCXA_MCXA366._ctimer_match.kCTIMER_Match_0 (*C enumerator*), 216
drivers_MCX_MCXA_MCXA366._ctimer_match.kCTIMER_Match_1 (*C enumerator*), 216
drivers_MCX_MCXA_MCXA366._ctimer_match.kCTIMER_Match_2 (*C enumerator*), 216
drivers_MCX_MCXA_MCXA366._ctimer_match.kCTIMER_Match_3 (*C enumerator*), 216
drivers_MCX_MCXA_MCXA366._ctimer_status_flags (*C enum*), 217
drivers_MCX_MCXA_MCXA366._ctimer_status_flags.kCTIMER_Match0Flag (*C enumerator*), 218
drivers_MCX_MCXA_MCXA366._ctimer_status_flags.kCTIMER_Match1Flag (*C enumerator*), 218
drivers_MCX_MCXA_MCXA366._ctimer_status_flags.kCTIMER_Match2Flag (*C enumerator*), 218
drivers_MCX_MCXA_MCXA366._ctimer_status_flags.kCTIMER_Match3Flag (*C enumerator*), 218
drivers_MCX_MCXA_MCXA366._ctimer_timer_mode (*C enum*), 217
drivers_MCX_MCXA_MCXA366._ctimer_timer_mode.kCTIMER_IncreaseOnBothEdge (*C enumerator*), 217
drivers_MCX_MCXA_MCXA366._ctimer_timer_mode.kCTIMER_IncreaseOnFallEdge (*C enumerator*), 217
drivers_MCX_MCXA_MCXA366._ctimer_timer_mode.kCTIMER_IncreaseOnRiseEdge (*C enumerator*), 217
drivers_MCX_MCXA_MCXA366._ctimer_timer_mode.kCTIMER_TimerMode (*C enumerator*), 217
drivers_MCX_MCXA_MCXA366._dac_config (*C struct*), 229
drivers_MCX_MCXA_MCXA366._dac_config.enableAnalogOutputBufferBypass (*C var*), 229
drivers_MCX_MCXA_MCXA366._dac_config.enableLowerLowPowerMode (*C var*), 229
drivers_MCX_MCXA_MCXA366._dac_config.enableOpampBuffer (*C var*), 229
drivers_MCX_MCXA_MCXA366._dac_config.fifoTriggerMode (*C var*), 229
drivers_MCX_MCXA_MCXA366._dac_config.fifoWatermarkLevel (*C var*), 229
drivers_MCX_MCXA_MCXA366._dac_config.fifoWorkMode (*C var*), 229
drivers_MCX_MCXA_MCXA366._dac_config.periodicTriggerNumber (*C var*), 229
drivers_MCX_MCXA_MCXA366._dac_config.periodicTriggerWidth (*C var*), 229
drivers_MCX_MCXA_MCXA366._dac_config.referenceCurrentSource (*C var*), 229
drivers_MCX_MCXA_MCXA366._dac_config.referenceCurrentTrim (*C var*), 229
drivers_MCX_MCXA_MCXA366._dac_config.referenceVoltageSource (*C var*), 230

drivers_MCX_MCXA_MCXA366._dac_config.syncTime (*C var*), 229
drivers_MCX_MCXA_MCXA366._dac_fifo_trigger_mode (*C enum*), 227
drivers_MCX_MCXA_MCXA366._dac_fifo_trigger_mode.kDAC_FIFOTriggerByHardwareMode (*C enumerator*), 227
drivers_MCX_MCXA_MCXA366._dac_fifo_trigger_mode.kDAC_FIFOTriggerBySoftwareMode (*C enumerator*), 227
drivers_MCX_MCXA_MCXA366._dac_fifo_work_mode (*C enum*), 227
drivers_MCX_MCXA_MCXA366._dac_fifo_work_mode.kDAC_FIFODisabled (*C enumerator*), 227
drivers_MCX_MCXA_MCXA366._dac_fifo_work_mode.kDAC_FIFOWorkAsNormalMode (*C enumerator*), 227
drivers_MCX_MCXA_MCXA366._dac_fifo_work_mode.kDAC_FIFOWorkAsPeriodTriggerAndSwingMode (*C enumerator*), 227
drivers_MCX_MCXA_MCXA366._dac_fifo_work_mode.kDAC_FIFOWorkAsPeriodTriggerMode (*C enumerator*), 227
drivers_MCX_MCXA_MCXA366._dac_fifo_work_mode.kDAC_FIFOWorkAsSwingMode (*C enumerator*), 227
drivers_MCX_MCXA_MCXA366._dac_reference_current_source (*C enum*), 228
drivers_MCX_MCXA_MCXA366._dac_reference_current_source.kDAC_ReferenceCurrentSourceInternal (*C enumerator*), 228
drivers_MCX_MCXA_MCXA366._dac_reference_current_source.kDAC_ReferenceCurrentSourcePtat (*C enumerator*), 228
drivers_MCX_MCXA_MCXA366._dac_reference_current_source.kDAC_ReferenceCurrentSourceZtc (*C enumerator*), 228
drivers_MCX_MCXA_MCXA366._dac_reference_current_trim (*C enum*), 228
drivers_MCX_MCXA_MCXA366._dac_reference_current_trim.kDAC_ReferenceCurrentTrimMinus25Percent (*C enumerator*), 228
drivers_MCX_MCXA_MCXA366._dac_reference_current_trim.kDAC_ReferenceCurrentTrimMinus125Percent (*C enumerator*), 228
drivers_MCX_MCXA_MCXA366._dac_reference_current_trim.kDAC_ReferenceCurrentTrimPlus25Percent (*C enumerator*), 228
drivers_MCX_MCXA_MCXA366._dac_reference_current_trim.kDAC_ReferenceCurrentTrimPlus125Percent (*C enumerator*), 228
drivers_MCX_MCXA_MCXA366._dac_reference_current_trim.kDAC_ReferenceCurrentTrimTypical (*C enumerator*), 228
drivers_MCX_MCXA_MCXA366._dac_reference_voltage_source (*C enum*), 227
drivers_MCX_MCXA_MCXA366._dac_reference_voltage_source.kDAC_ReferenceVoltageSourceAlt1 (*C enumerator*), 228
drivers_MCX_MCXA_MCXA366._dac_reference_voltage_source.kDAC_ReferenceVoltageSourceAlt2 (*C enumerator*), 228
drivers_MCX_MCXA_MCXA366._edma4_core_tcd (*C struct*), 270
drivers_MCX_MCXA_MCXA366._edma5_core_tcd (*C struct*), 269
drivers_MCX_MCXA_MCXA366._edma5_core_tcd.RESERVED (*C var*), 270
drivers_MCX_MCXA_MCXA366._edma_bandwidth (*C enum*), 252
drivers_MCX_MCXA_MCXA366._edma_bandwidth.kEDMA_BandwidthStall4Cycle (*C enumerator*), 252
drivers_MCX_MCXA_MCXA366._edma_bandwidth.kEDMA_BandwidthStall8Cycle (*C enumerator*), 252
drivers_MCX_MCXA_MCXA366._edma_bandwidth.kEDMA_BandwidthStallNone (*C enumerator*), 252
drivers_MCX_MCXA_MCXA366._edma_channel_access_type (*C enum*), 256
drivers_MCX_MCXA_MCXA366._edma_channel_access_type.kEDMA_ChannelDataAccess (*C enumerator*), 256
drivers_MCX_MCXA_MCXA366._edma_channel_access_type.kEDMA_ChannelInstructionAccess (*C enumerator*), 256
drivers_MCX_MCXA_MCXA366._edma_channel_config (*C struct*), 259
drivers_MCX_MCXA_MCXA366._edma_channel_config.channelAccessType (*C var*), 260
drivers_MCX_MCXA_MCXA366._edma_channel_config.channelDataSignExtensionBitPosition (*C var*), 260

drivers_MCX_MCXA_MCXA366._edma_channel_config.channelPreemptionConfig (*C var*), 259
drivers_MCX_MCXA_MCXA366._edma_channel_config.channelReadMemoryAttribute (*C var*), 259
drivers_MCX_MCXA_MCXA366._edma_channel_config.channelRequestSource (*C var*), 260
drivers_MCX_MCXA_MCXA366._edma_channel_config.channelSwapSize (*C var*), 260
drivers_MCX_MCXA_MCXA366._edma_channel_config.channelWriteMemoryAttribute (*C var*), 259
drivers_MCX_MCXA_MCXA366._edma_channel_config.enableMasterIDReplication (*C var*), 260
drivers_MCX_MCXA_MCXA366._edma_channel_config.protectionLevel (*C var*), 260
drivers_MCX_MCXA_MCXA366._edma_channel_link_type (*C enum*), 252
drivers_MCX_MCXA_MCXA366._edma_channel_link_type.kEDMA_LinkNone (*C enumerator*), 252
drivers_MCX_MCXA_MCXA366._edma_channel_link_type.kEDMA_MajorLink (*C enumerator*), 252
drivers_MCX_MCXA_MCXA366._edma_channel_link_type.kEDMA_MinorLink (*C enumerator*), 252
drivers_MCX_MCXA_MCXA366._edma_channel_Preemption_config (*C struct*), 259
drivers_MCX_MCXA_MCXA366._edma_channel_Preemption_config.channelPriority (*C var*), 259
drivers_MCX_MCXA_MCXA366._edma_channel_Preemption_config.enableChannelPreemption (*C var*), 259
drivers_MCX_MCXA_MCXA366._edma_channel_Preemption_config.enablePreemptAbility (*C var*), 259
drivers_MCX_MCXA_MCXA366._edma_channel_protection_level (*C enum*), 256
drivers_MCX_MCXA_MCXA366._edma_channel_protection_level.kEDMA_ChannelProtectionLevelPrivileged (*C enumerator*), 256
drivers_MCX_MCXA_MCXA366._edma_channel_protection_level.kEDMA_ChannelProtectionLevelUser (*C enumerator*), 256
drivers_MCX_MCXA_MCXA366._edma_channel_swap_size (*C enum*), 255
drivers_MCX_MCXA_MCXA366._edma_channel_swap_size.kEDMA_ChannelReadWith8bitSwap (*C enumerator*), 255
drivers_MCX_MCXA_MCXA366._edma_channel_swap_size.kEDMA_ChannelReadWith16bitSwap (*C enumerator*), 255
drivers_MCX_MCXA_MCXA366._edma_channel_swap_size.kEDMA_ChannelReadWith32bitSwap (*C enumerator*), 255
drivers_MCX_MCXA_MCXA366._edma_channel_swap_size.kEDMA_ChannelSwapDisabled (*C enumerator*), 255
drivers_MCX_MCXA_MCXA366._edma_channel_swap_size.kEDMA_ChannelWriteWith8bitSwap (*C enumerator*), 255
drivers_MCX_MCXA_MCXA366._edma_channel_swap_size.kEDMA_ChannelWriteWith16bitSwap (*C enumerator*), 255
drivers_MCX_MCXA_MCXA366._edma_channel_swap_size.kEDMA_ChannelWriteWith32bitSwap (*C enumerator*), 256
drivers_MCX_MCXA_MCXA366._edma_config (*C struct*), 262
drivers_MCX_MCXA_MCXA366._edma_config.channelConfig (*C var*), 263
drivers_MCX_MCXA_MCXA366._edma_config.enableDebugMode (*C var*), 262
drivers_MCX_MCXA_MCXA366._edma_config.enableGlobalChannelLink (*C var*), 262
drivers_MCX_MCXA_MCXA366._edma_config.enableHaltOnError (*C var*), 262
drivers_MCX_MCXA_MCXA366._edma_config.enableMasterIdReplication (*C var*), 262
drivers_MCX_MCXA_MCXA366._edma_config.enableRoundRobinArbitration (*C var*), 262
drivers_MCX_MCXA_MCXA366._edma_core_channel (*C struct*), 269
drivers_MCX_MCXA_MCXA366._edma_core_channel.CH_REGS (*C union*), 272
drivers_MCX_MCXA_MCXA366._edma_core_channel.CH_REGS.EDMA4_REG (*C struct*), 272
drivers_MCX_MCXA_MCXA366._edma_core_channel.CH_REGS.EDMA4_REG (*C var*), 272
drivers_MCX_MCXA_MCXA366._edma_core_channel.CH_REGS.EDMA5_REG (*C struct*), 272
drivers_MCX_MCXA_MCXA366._edma_core_channel.CH_REGS.EDMA5_REG (*C var*), 272
drivers_MCX_MCXA_MCXA366._edma_core_mp (*C struct*), 268
drivers_MCX_MCXA_MCXA366._edma_core_mp.MP_REGS (*C union*), 271
drivers_MCX_MCXA_MCXA366._edma_core_mp.MP_REGS.EDMA5_REG (*C struct*), 271
drivers_MCX_MCXA_MCXA366._edma_core_mp.MP_REGS.EDMA5_REG (*C var*), 271
drivers_MCX_MCXA_MCXA366._edma_core_tcd (*C struct*), 271

drivers_MCX_MCXA_MCXA366._edma_core_tcd.TCD_REGS (*C union*), 272
drivers_MCX_MCXA_MCXA366._edma_core_tcd.TCD_REGS.edma4_tcd (*C var*), 273
drivers_MCX_MCXA_MCXA366._edma_handle (*C struct*), 263
drivers_MCX_MCXA_MCXA366._edma_handle.base (*C var*), 263
drivers_MCX_MCXA_MCXA366._edma_handle.callback (*C var*), 263
drivers_MCX_MCXA_MCXA366._edma_handle.channel (*C var*), 263
drivers_MCX_MCXA_MCXA366._edma_handle.channelBase (*C var*), 263
drivers_MCX_MCXA_MCXA366._edma_handle.header (*C var*), 263
drivers_MCX_MCXA_MCXA366._edma_handle.tail (*C var*), 263
drivers_MCX_MCXA_MCXA366._edma_handle.tcdBase (*C var*), 263
drivers_MCX_MCXA_MCXA366._edma_handle.tcdPool (*C var*), 263
drivers_MCX_MCXA_MCXA366._edma_handle.tcdSize (*C var*), 263
drivers_MCX_MCXA_MCXA366._edma_handle.tcdUsed (*C var*), 263
drivers_MCX_MCXA_MCXA366._edma_handle.userData (*C var*), 263
drivers_MCX_MCXA_MCXA366._edma_minor_offset_config (*C struct*), 259
drivers_MCX_MCXA_MCXA366._edma_minor_offset_config.enableDestMinorOffset (*C var*), 259
drivers_MCX_MCXA_MCXA366._edma_minor_offset_config.enableSrcMinorOffset (*C var*), 259
drivers_MCX_MCXA_MCXA366._edma_minor_offset_config.minorOffset (*C var*), 259
drivers_MCX_MCXA_MCXA366._edma_modulo (*C enum*), 250
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo1Gbytes (*C enumerator*), 252
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo1Kbytes (*C enumerator*), 250
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo1Mbytes (*C enumerator*), 251
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo2bytes (*C enumerator*), 250
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo2Gbytes (*C enumerator*), 252
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo2Kbytes (*C enumerator*), 251
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo2Mbytes (*C enumerator*), 251
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo4bytes (*C enumerator*), 250
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo4Kbytes (*C enumerator*), 251
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo4Mbytes (*C enumerator*), 251
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo8bytes (*C enumerator*), 250
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo8Kbytes (*C enumerator*), 251
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo8Mbytes (*C enumerator*), 251
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo16bytes (*C enumerator*), 250
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo16Kbytes (*C enumerator*), 251
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo16Mbytes (*C enumerator*), 251
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo32bytes (*C enumerator*), 250
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo32Kbytes (*C enumerator*), 251
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo32Mbytes (*C enumerator*), 251
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo64bytes (*C enumerator*), 250
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo64Kbytes (*C enumerator*), 251
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo64Mbytes (*C enumerator*), 251
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo128bytes (*C enumerator*), 250
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo128Kbytes (*C enumerator*), 251
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo128Mbytes (*C enumerator*), 252
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo256bytes (*C enumerator*), 250
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo256Kbytes (*C enumerator*), 251
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo256Mbytes (*C enumerator*), 252
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo512bytes (*C enumerator*), 250
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo512Kbytes (*C enumerator*), 251
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_Modulo512Mbytes (*C enumerator*), 252
drivers_MCX_MCXA_MCXA366._edma_modulo.kEDMA_ModuloDisable (*C enumerator*), 250
drivers_MCX_MCXA_MCXA366._edma_tcd_type (*C enum*), 264
drivers_MCX_MCXA_MCXA366._edma_tcd_type.kEDMA_EDMA4Flag (*C enumerator*), 264
drivers_MCX_MCXA_MCXA366._edma_tcd_type.kEDMA_EDMA5Flag (*C enumerator*), 264
drivers_MCX_MCXA_MCXA366._edma_transfer_config (*C struct*), 260
drivers_MCX_MCXA_MCXA366._edma_transfer_config.destAddr (*C var*), 261
drivers_MCX_MCXA_MCXA366._edma_transfer_config.destOffset (*C var*), 261
drivers_MCX_MCXA_MCXA366._edma_transfer_config.destTransferSize (*C var*), 261

drivers_MCX_MCXA_MCXA366._edma_transfer_config.dstAddrModulo (*C var*), 261
drivers_MCX_MCXA_MCXA366._edma_transfer_config.dstMajorLoopOffset (*C var*), 261
drivers_MCX_MCXA_MCXA366._edma_transfer_config.enableChannelMajorLoopLink (*C var*), 262
drivers_MCX_MCXA_MCXA366._edma_transfer_config.enableChannelMinorLoopLink (*C var*), 262
drivers_MCX_MCXA_MCXA366._edma_transfer_config.enabledInterruptMask (*C var*), 261
drivers_MCX_MCXA_MCXA366._edma_transfer_config.enableDstMinorLoopOffset (*C var*), 262
drivers_MCX_MCXA_MCXA366._edma_transfer_config.enableSrcMinorLoopOffset (*C var*), 262
drivers_MCX_MCXA_MCXA366._edma_transfer_config.linkTCD (*C var*), 262
drivers_MCX_MCXA_MCXA366._edma_transfer_config.majorLoopCounts (*C var*), 261
drivers_MCX_MCXA_MCXA366._edma_transfer_config.majorLoopLinkChannel (*C var*), 262
drivers_MCX_MCXA_MCXA366._edma_transfer_config.minorLoopBytes (*C var*), 261
drivers_MCX_MCXA_MCXA366._edma_transfer_config.minorLoopLinkChannel (*C var*), 262
drivers_MCX_MCXA_MCXA366._edma_transfer_config.minorLoopOffset (*C var*), 262
drivers_MCX_MCXA_MCXA366._edma_transfer_config.srcAddr (*C var*), 261
drivers_MCX_MCXA_MCXA366._edma_transfer_config.srcAddrModulo (*C var*), 261
drivers_MCX_MCXA_MCXA366._edma_transfer_config.srcMajorLoopOffset (*C var*), 261
drivers_MCX_MCXA_MCXA366._edma_transfer_config.srcOffset (*C var*), 261
drivers_MCX_MCXA_MCXA366._edma_transfer_config.srcTransferSize (*C var*), 261
drivers_MCX_MCXA_MCXA366._edma_transfer_size (*C enum*), 249
drivers_MCX_MCXA_MCXA366._edma_transfer_size.kEDMA_TransferSize1Bytes (*C enumerator*), 249
drivers_MCX_MCXA_MCXA366._edma_transfer_size.kEDMA_TransferSize2Bytes (*C enumerator*), 249
drivers_MCX_MCXA_MCXA366._edma_transfer_size.kEDMA_TransferSize4Bytes (*C enumerator*), 249
drivers_MCX_MCXA_MCXA366._edma_transfer_size.kEDMA_TransferSize8Bytes (*C enumerator*), 249
drivers_MCX_MCXA_MCXA366._edma_transfer_size.kEDMA_TransferSize16Bytes (*C enumerator*), 250
drivers_MCX_MCXA_MCXA366._edma_transfer_size.kEDMA_TransferSize32Bytes (*C enumerator*), 250
drivers_MCX_MCXA_MCXA366._edma_transfer_size.kEDMA_TransferSize64Bytes (*C enumerator*), 250
drivers_MCX_MCXA_MCXA366._edma_transfer_size.kEDMA_TransferSize128Bytes (*C enumerator*), 250
drivers_MCX_MCXA_MCXA366._edma_transfer_type (*C enum*), 254
drivers_MCX_MCXA_MCXA366._edma_transfer_type.kEDMA_MemoryToMemory (*C enumerator*), 254
drivers_MCX_MCXA_MCXA366._edma_transfer_type.kEDMA_MemoryToPeripheral (*C enumerator*), 254
drivers_MCX_MCXA_MCXA366._edma_transfer_type.kEDMA_PeripheralToMemory (*C enumerator*), 254
drivers_MCX_MCXA_MCXA366._edma_transfer_type.kEDMA_PeripheralToPeripheral (*C enumerator*), 254
drivers_MCX_MCXA_MCXA366._eqdc_config (*C struct*), 290
drivers_MCX_MCXA_MCXA366._eqdc_config.bufferedRegisterLoadMode (*C var*), 290
drivers_MCX_MCXA_MCXA366._eqdc_config.countMode (*C var*), 292
drivers_MCX_MCXA_MCXA366._eqdc_config.countOnce (*C var*), 290
drivers_MCX_MCXA_MCXA366._eqdc_config.enabledInterruptsMask (*C var*), 293
drivers_MCX_MCXA_MCXA366._eqdc_config.enableDma (*C var*), 290
drivers_MCX_MCXA_MCXA366._eqdc_config.enableIndexInitPositionCounter (*C var*), 291
drivers_MCX_MCXA_MCXA366._eqdc_config.enablePeriodMeasurement (*C var*), 293
drivers_MCX_MCXA_MCXA366._eqdc_config.enableReverseDirection (*C var*), 290
drivers_MCX_MCXA_MCXA366._eqdc_config.enableTriggerClearPositionRegisters (*C var*), 291
drivers_MCX_MCXA_MCXA366._eqdc_config.enableTriggerHoldPositionRegisters (*C var*), 291
drivers_MCX_MCXA_MCXA366._eqdc_config.enableTriggerInitPositionCounter (*C var*), 291
drivers_MCX_MCXA_MCXA366._eqdc_config.enableWatchdog (*C var*), 291
drivers_MCX_MCXA_MCXA366._eqdc_config.filterClockSourceselection (*C var*), 292

drivers_MCX_MCXA_MCXA366._eqdc_config.filterHomEna (*C var*), 291
drivers_MCX_MCXA_MCXA366._eqdc_config.filterIndPre (*C var*), 291
drivers_MCX_MCXA_MCXA366._eqdc_config.filterPhaseA (*C var*), 291
drivers_MCX_MCXA_MCXA366._eqdc_config.filterPhaseB (*C var*), 291
drivers_MCX_MCXA_MCXA366._eqdc_config.filterSampleCount (*C var*), 292
drivers_MCX_MCXA_MCXA366._eqdc_config.filterSamplePeriod (*C var*), 292
drivers_MCX_MCXA_MCXA366._eqdc_config.homeEnableInitPosCounterMode (*C var*), 292
drivers_MCX_MCXA_MCXA366._eqdc_config.indexPresetInitPosCounterMode (*C var*), 292
drivers_MCX_MCXA_MCXA366._eqdc_config.operateMode (*C var*), 292
drivers_MCX_MCXA_MCXA366._eqdc_config.outputPulseMode (*C var*), 292
drivers_MCX_MCXA_MCXA366._eqdc_config.positionCompareValue (*C var*), 292
drivers_MCX_MCXA_MCXA366._eqdc_config.positionCounterValue (*C var*), 292
drivers_MCX_MCXA_MCXA366._eqdc_config.positionInitialValue (*C var*), 292
drivers_MCX_MCXA_MCXA366._eqdc_config.positionModulusValue (*C var*), 292
drivers_MCX_MCXA_MCXA366._eqdc_config.prescaler (*C var*), 292
drivers_MCX_MCXA_MCXA366._eqdc_config.revolutionCountCondition (*C var*), 292
drivers_MCX_MCXA_MCXA366._eqdc_config.watchdogTimeoutValue (*C var*), 292
drivers_MCX_MCXA_MCXA366._eqdc_count_direction_flag (*C enum*), 287
drivers_MCX_MCXA_MCXA366._eqdc_count_direction_flag.kEQDC_CountDirectionDown (*C enumerator*), 287
drivers_MCX_MCXA_MCXA366._eqdc_count_direction_flag.kEQDC_CountDirectionUp (*C enumerator*), 287
drivers_MCX_MCXA_MCXA366._eqdc_count_mode (*C enum*), 285
drivers_MCX_MCXA_MCXA366._eqdc_count_mode.kEQDC_QuadratureX1 (*C enumerator*), 286
drivers_MCX_MCXA_MCXA366._eqdc_count_mode.kEQDC_QuadratureX2 (*C enumerator*), 286
drivers_MCX_MCXA_MCXA366._eqdc_count_mode.kEQDC_QuadratureX4 (*C enumerator*), 286
drivers_MCX_MCXA_MCXA366._eqdc_count_mode.kEQDC_SignedCountDoubleEdge (*C enumerator*), 286
drivers_MCX_MCXA_MCXA366._eqdc_count_mode.kEQDC_SignedCountSingleEdge (*C enumerator*), 286
drivers_MCX_MCXA_MCXA366._eqdc_count_mode.kEQDC_UpDownPulseCount (*C enumerator*), 286
drivers_MCX_MCXA_MCXA366._eqdc_filter_sample_count (*C enum*), 287
drivers_MCX_MCXA_MCXA366._eqdc_filter_sample_count.kEQDC_Filter3Samples (*C enumerator*), 287
drivers_MCX_MCXA_MCXA366._eqdc_filter_sample_count.kEQDC_Filter4Samples (*C enumerator*), 287
drivers_MCX_MCXA_MCXA366._eqdc_filter_sample_count.kEQDC_Filter5Samples (*C enumerator*), 287
drivers_MCX_MCXA_MCXA366._eqdc_filter_sample_count.kEQDC_Filter6Samples (*C enumerator*), 287
drivers_MCX_MCXA_MCXA366._eqdc_filter_sample_count.kEQDC_Filter7Samples (*C enumerator*), 287
drivers_MCX_MCXA_MCXA366._eqdc_filter_sample_count.kEQDC_Filter8Samples (*C enumerator*), 287
drivers_MCX_MCXA_MCXA366._eqdc_filter_sample_count.kEQDC_Filter9Samples (*C enumerator*), 287
drivers_MCX_MCXA_MCXA366._eqdc_filter_sample_count.kEQDC_Filter10Samples (*C enumerator*), 287
drivers_MCX_MCXA_MCXA366._eqdc_home_enable_init_pos_counter_mode (*C enum*), 284
drivers_MCX_MCXA_MCXA366._eqdc_home_enable_init_pos_counter_mode.kEQDC_HomeInitPosCounterDisab (*C enumerator*), 284
drivers_MCX_MCXA_MCXA366._eqdc_home_enable_init_pos_counter_mode.kEQDC_HomeInitPosCounterOnFa (*C enumerator*), 284
drivers_MCX_MCXA_MCXA366._eqdc_home_enable_init_pos_counter_mode.kEQDC_HomeInitPosCounterOnRi (*C enumerator*), 284
drivers_MCX_MCXA_MCXA366._eqdc_index_preset_init_pos_counter_mode (*C enum*), 284
drivers_MCX_MCXA_MCXA366._eqdc_index_preset_init_pos_counter_mode.kEQDC_IndexInitPosCounterDisab

(*C enumerator*), 285
drivers_MCX_MCXA_MCXA366._eqdc_index_preset_init_pos_counter_mode.kEQDC_IndexInitPosCounterOnFa
(*C enumerator*), 285
drivers_MCX_MCXA_MCXA366._eqdc_index_preset_init_pos_counter_mode.kEQDC_IndexInitPosCounterOnRis
(*C enumerator*), 285
drivers_MCX_MCXA_MCXA366._eqdc_interrupt_enable (*C enum*), 284
drivers_MCX_MCXA_MCXA366._eqdc_interrupt_enable.kEQDC_AllInterruptEnable (*C enumerator*), 284
drivers_MCX_MCXA_MCXA366._eqdc_interrupt_enable.kEQDC_CountDirectionChangeInterruptEnable
(*C enumerator*), 284
drivers_MCX_MCXA_MCXA366._eqdc_interrupt_enable.kEQDC_HomeEnableTransitionInterruptEnable
(*C enumerator*), 284
drivers_MCX_MCXA_MCXA366._eqdc_interrupt_enable.kEQDC_IndexPresetPulseInterruptEnable
(*C enumerator*), 284
drivers_MCX_MCXA_MCXA366._eqdc_interrupt_enable.kEQDC_PositionRollOverInterruptEnable
(*C enumerator*), 284
drivers_MCX_MCXA_MCXA366._eqdc_interrupt_enable.kEQDC_PositionRollUnderInterruptEnable
(*C enumerator*), 284
drivers_MCX_MCXA_MCXA366._eqdc_interrupt_enable.kEQDC_SimultPhaseChangeInterruptEnable
(*C enumerator*), 284
drivers_MCX_MCXA_MCXA366._eqdc_interrupt_enable.kEQDC_WatchdogTimeoutInterruptEnable
(*C enumerator*), 284
drivers_MCX_MCXA_MCXA366._eqdc_operate_mode (*C enum*), 285
drivers_MCX_MCXA_MCXA366._eqdc_operate_mode.kEQDC_QuadratureCountOperationMode
(*C enumerator*), 285
drivers_MCX_MCXA_MCXA366._eqdc_operate_mode.kEQDC_QuadratureDecodeOperationMode
(*C enumerator*), 285
drivers_MCX_MCXA_MCXA366._eqdc_operate_mode.kEQDC_SinglePhaseCountOperationMode
(*C enumerator*), 285
drivers_MCX_MCXA_MCXA366._eqdc_operate_mode.kEQDC_SinglePhaseDecodeOperationMode
(*C enumerator*), 285
drivers_MCX_MCXA_MCXA366._eqdc_output_pulse_mode (*C enum*), 286
drivers_MCX_MCXA_MCXA366._eqdc_output_pulse_mode.kEQDC_OutputPulseOnCounterEqualCompare
(*C enumerator*), 286
drivers_MCX_MCXA_MCXA366._eqdc_output_pulse_mode.kEQDC_OutputPulseOnReadingPositionCounter
(*C enumerator*), 286
drivers_MCX_MCXA_MCXA366._eqdc_prescaler (*C enum*), 287
drivers_MCX_MCXA_MCXA366._eqdc_prescaler.kEQDC_Prescaler1 (*C enumerator*), 287
drivers_MCX_MCXA_MCXA366._eqdc_prescaler.kEQDC_Prescaler2 (*C enumerator*), 288
drivers_MCX_MCXA_MCXA366._eqdc_prescaler.kEQDC_Prescaler4 (*C enumerator*), 288
drivers_MCX_MCXA_MCXA366._eqdc_prescaler.kEQDC_Prescaler8 (*C enumerator*), 288
drivers_MCX_MCXA_MCXA366._eqdc_prescaler.kEQDC_Prescaler16 (*C enumerator*), 288
drivers_MCX_MCXA_MCXA366._eqdc_prescaler.kEQDC_Prescaler32 (*C enumerator*), 288
drivers_MCX_MCXA_MCXA366._eqdc_prescaler.kEQDC_Prescaler64 (*C enumerator*), 288
drivers_MCX_MCXA_MCXA366._eqdc_prescaler.kEQDC_Prescaler128 (*C enumerator*), 288
drivers_MCX_MCXA_MCXA366._eqdc_prescaler.kEQDC_Prescaler256 (*C enumerator*), 288
drivers_MCX_MCXA_MCXA366._eqdc_prescaler.kEQDC_Prescaler512 (*C enumerator*), 288
drivers_MCX_MCXA_MCXA366._eqdc_prescaler.kEQDC_Prescaler1024 (*C enumerator*), 288
drivers_MCX_MCXA_MCXA366._eqdc_prescaler.kEQDC_Prescaler2048 (*C enumerator*), 288
drivers_MCX_MCXA_MCXA366._eqdc_prescaler.kEQDC_Prescaler4096 (*C enumerator*), 288
drivers_MCX_MCXA_MCXA366._eqdc_prescaler.kEQDC_Prescaler8192 (*C enumerator*), 288
drivers_MCX_MCXA_MCXA366._eqdc_prescaler.kEQDC_Prescaler16384 (*C enumerator*), 288
drivers_MCX_MCXA_MCXA366._eqdc_prescaler.kEQDC_Prescaler32768 (*C enumerator*), 288
drivers_MCX_MCXA_MCXA366._eqdc_revolution_count_condition (*C enum*), 286
drivers_MCX_MCXA_MCXA366._eqdc_revolution_count_condition.kEQDC_RevolutionCountOnIndexPulse
(*C enumerator*), 286
drivers_MCX_MCXA_MCXA366._eqdc_revolution_count_condition.kEQDC_RevolutionCountOnRollOverModulus
(*C enumerator*), 286

drivers_MCX_MCXA_MCXA366._eqdc_signal_status (*C enum*), 283
drivers_MCX_MCXA_MCXA366._eqdc_signal_status.kEQDC_SignalStatusAllFlags (*C enumerator*), 284
drivers_MCX_MCXA_MCXA366._eqdc_signal_status.kEQDC_SignalStatusCountDirectionFlag (*C enumerator*), 284
drivers_MCX_MCXA_MCXA366._eqdc_signal_status.kEQDC_SignalStatusCountDirectionFlagHold (*C enumerator*), 283
drivers_MCX_MCXA_MCXA366._eqdc_signal_status.kEQDC_SignalStatusFilteredHomeEnable (*C enumerator*), 283
drivers_MCX_MCXA_MCXA366._eqdc_signal_status.kEQDC_SignalStatusFilteredIndexPreset (*C enumerator*), 283
drivers_MCX_MCXA_MCXA366._eqdc_signal_status.kEQDC_SignalStatusFilteredPhaseA (*C enumerator*), 283
drivers_MCX_MCXA_MCXA366._eqdc_signal_status.kEQDC_SignalStatusFilteredPhaseB (*C enumerator*), 283
drivers_MCX_MCXA_MCXA366._eqdc_signal_status.kEQDC_SignalStatusPositionCompare0Flag (*C enumerator*), 283
drivers_MCX_MCXA_MCXA366._eqdc_signal_status.kEQDC_SignalStatusPositionCompare1Flag (*C enumerator*), 283
drivers_MCX_MCXA_MCXA366._eqdc_signal_status.kEQDC_SignalStatusPositionCompare2Flag (*C enumerator*), 283
drivers_MCX_MCXA_MCXA366._eqdc_signal_status.kEQDC_SignalStatusPositionCompare3Flag (*C enumerator*), 283
drivers_MCX_MCXA_MCXA366._eqdc_signal_status.kEQDC_SignalStatusRawHomeEnable (*C enumerator*), 283
drivers_MCX_MCXA_MCXA366._eqdc_signal_status.kEQDC_SignalStatusRawIndexPreset (*C enumerator*), 283
drivers_MCX_MCXA_MCXA366._eqdc_signal_status.kEQDC_SignalStatusRawPhaseA (*C enumerator*), 283
drivers_MCX_MCXA_MCXA366._eqdc_signal_status.kEQDC_SignalStatusRawPhaseB (*C enumerator*), 283
drivers_MCX_MCXA_MCXA366._eqdc_status_flags (*C enum*), 282
drivers_MCX_MCXA_MCXA366._eqdc_status_flags.kEQDC_CountDirectionChangeFlag (*C enumerator*), 282
drivers_MCX_MCXA_MCXA366._eqdc_status_flags.kEQDC_HomeEnableTransitionFlag (*C enumerator*), 282
drivers_MCX_MCXA_MCXA366._eqdc_status_flags.kEQDC_IndexPresetPulseFlag (*C enumerator*), 282
drivers_MCX_MCXA_MCXA366._eqdc_status_flags.kEQDC_PositionCompare0Flag (*C enumerator*), 282
drivers_MCX_MCXA_MCXA366._eqdc_status_flags.kEQDC_PositionCompare1Flag (*C enumerator*), 282
drivers_MCX_MCXA_MCXA366._eqdc_status_flags.kEQDC_PositionCompare2Flag (*C enumerator*), 282
drivers_MCX_MCXA_MCXA366._eqdc_status_flags.kEQDC_PositionCompare3Flag (*C enumerator*), 283
drivers_MCX_MCXA_MCXA366._eqdc_status_flags.kEQDC_PositionRollOverFlag (*C enumerator*), 282
drivers_MCX_MCXA_MCXA366._eqdc_status_flags.kEQDC_PositionRollUnderFlag (*C enumerator*), 282
drivers_MCX_MCXA_MCXA366._eqdc_status_flags.kEQDC_SimultPhaseChangeFlag (*C enumerator*), 282
drivers_MCX_MCXA_MCXA366._eqdc_status_flags.kEQDC_StatusAllFlags (*C enumerator*), 283
drivers_MCX_MCXA_MCXA366._eqdc_status_flags.kEQDC_WatchdogTimeoutFlag (*C enumerator*), 282
drivers_MCX_MCXA_MCXA366._flexcan_byte_error_syndrome (*C enum*), 327
drivers_MCX_MCXA_MCXA366._flexcan_byte_error_syndrome.kFLEXCAN_AllOneError (*C enumerator*), 328

drivers_MCX_MCXA_MCXA366._flexcan_byte_error_syndrome.kFLEXCAN_AllZeroError (*C enumerator*), 328
drivers_MCX_MCXA_MCXA366._flexcan_byte_error_syndrome.kFLEXCAN_DataBits0Error (*C enumerator*), 328
drivers_MCX_MCXA_MCXA366._flexcan_byte_error_syndrome.kFLEXCAN_DataBits1Error (*C enumerator*), 328
drivers_MCX_MCXA_MCXA366._flexcan_byte_error_syndrome.kFLEXCAN_DataBits2Error (*C enumerator*), 328
drivers_MCX_MCXA_MCXA366._flexcan_byte_error_syndrome.kFLEXCAN_DataBits3Error (*C enumerator*), 328
drivers_MCX_MCXA_MCXA366._flexcan_byte_error_syndrome.kFLEXCAN_DataBits4Error (*C enumerator*), 328
drivers_MCX_MCXA_MCXA366._flexcan_byte_error_syndrome.kFLEXCAN_DataBits5Error (*C enumerator*), 328
drivers_MCX_MCXA_MCXA366._flexcan_byte_error_syndrome.kFLEXCAN_DataBits6Error (*C enumerator*), 328
drivers_MCX_MCXA_MCXA366._flexcan_byte_error_syndrome.kFLEXCAN_DataBits7Error (*C enumerator*), 328
drivers_MCX_MCXA_MCXA366._flexcan_byte_error_syndrome.kFLEXCAN_NoError (*C enumerator*), 327
drivers_MCX_MCXA_MCXA366._flexcan_byte_error_syndrome.kFLEXCAN_NonCorrectableErrors (*C enumerator*), 328
drivers_MCX_MCXA_MCXA366._flexcan_byte_error_syndrome.kFLEXCAN_ParityBits0Error (*C enumerator*), 328
drivers_MCX_MCXA_MCXA366._flexcan_byte_error_syndrome.kFLEXCAN_ParityBits1Error (*C enumerator*), 328
drivers_MCX_MCXA_MCXA366._flexcan_byte_error_syndrome.kFLEXCAN_ParityBits2Error (*C enumerator*), 328
drivers_MCX_MCXA_MCXA366._flexcan_byte_error_syndrome.kFLEXCAN_ParityBits3Error (*C enumerator*), 328
drivers_MCX_MCXA_MCXA366._flexcan_byte_error_syndrome.kFLEXCAN_ParityBits4Error (*C enumerator*), 328
drivers_MCX_MCXA_MCXA366._flexcan_capture_point (*C enum*), 319
drivers_MCX_MCXA_MCXA366._flexcan_capture_point.kFLEXCAN_CANFDFrameRes (*C enumerator*), 319
drivers_MCX_MCXA_MCXA366._flexcan_capture_point.kFLEXCAN_CANFrameEnd (*C enumerator*), 319
drivers_MCX_MCXA_MCXA366._flexcan_capture_point.kFLEXCAN_CANFrameID2ndBit (*C enumerator*), 319
drivers_MCX_MCXA_MCXA366._flexcan_capture_point.kFLEXCAN_CANFrameStart (*C enumerator*), 319
drivers_MCX_MCXA_MCXA366._flexcan_clock_source (*C enum*), 318
drivers_MCX_MCXA_MCXA366._flexcan_clock_source.kFLEXCAN_ClkSrc0 (*C enumerator*), 318
drivers_MCX_MCXA_MCXA366._flexcan_clock_source.kFLEXCAN_ClkSrc1 (*C enumerator*), 318
drivers_MCX_MCXA_MCXA366._flexcan_clock_source.kFLEXCAN_ClkSrcOsc (*C enumerator*), 318
drivers_MCX_MCXA_MCXA366._flexcan_clock_source.kFLEXCAN_ClkSrcPeri (*C enumerator*), 318
drivers_MCX_MCXA_MCXA366._flexcan_config (*C struct*), 337
drivers_MCX_MCXA_MCXA366._flexcan_config.___unnamed42___ (*C union*), 347
drivers_MCX_MCXA_MCXA366._flexcan_config.___unnamed42___.___unnamed44___ (*C struct*), 347
drivers_MCX_MCXA_MCXA366._flexcan_config.___unnamed42___.___unnamed44___.baudRate (*C var*), 348
drivers_MCX_MCXA_MCXA366._flexcan_config.___unnamed42___.___unnamed44___.baudRateFD (*C var*), 348
drivers_MCX_MCXA_MCXA366._flexcan_config.___unnamed42___.___unnamed46___ (*C struct*), 348

drivers_MCX_MCXA_MCXA366._flexcan_config.___unnamed42___.___unnamed46___.bitRate (C var), 348
drivers_MCX_MCXA_MCXA366._flexcan_config.___unnamed42___.___unnamed46___.bitRateFD (C var), 348
drivers_MCX_MCXA_MCXA366._flexcan_config.capturePoint (C var), 338
drivers_MCX_MCXA_MCXA366._flexcan_config.captureTimeBase (C var), 338
drivers_MCX_MCXA_MCXA366._flexcan_config.clkSrc (C var), 337
drivers_MCX_MCXA_MCXA366._flexcan_config.disableBusOffAutoRecovery (C var), 338
drivers_MCX_MCXA_MCXA366._flexcan_config.disableSelfReception (C var), 337
drivers_MCX_MCXA_MCXA366._flexcan_config.enableDoze (C var), 337
drivers_MCX_MCXA_MCXA366._flexcan_config.enableEntireArbitrationCompare (C var), 338
drivers_MCX_MCXA_MCXA366._flexcan_config.enableExternalTimeTick (C var), 338
drivers_MCX_MCXA_MCXA366._flexcan_config.enableIndividMask (C var), 337
drivers_MCX_MCXA_MCXA366._flexcan_config.enableListenOnlyMode (C var), 337
drivers_MCX_MCXA_MCXA366._flexcan_config.enableLoopBack (C var), 337
drivers_MCX_MCXA_MCXA366._flexcan_config.enableMemoryErrorControl (C var), 338
drivers_MCX_MCXA_MCXA366._flexcan_config.enableNonCorrectableErrorEnterFreeze (C var), 338
drivers_MCX_MCXA_MCXA366._flexcan_config.enablePretendedeNetworking (C var), 338
drivers_MCX_MCXA_MCXA366._flexcan_config.enableRemoteRequestFrameStored (C var), 338
drivers_MCX_MCXA_MCXA366._flexcan_config.enableThreeSamplingMode (C var), 338
drivers_MCX_MCXA_MCXA366._flexcan_config.enableTimerSync (C var), 337
drivers_MCX_MCXA_MCXA366._flexcan_config.enableTransceiverDelayMeasure (C var), 338
drivers_MCX_MCXA_MCXA366._flexcan_config.maxMbNum (C var), 337
drivers_MCX_MCXA_MCXA366._flexcan_config.payloadEndianness (C var), 338
drivers_MCX_MCXA_MCXA366._flexcan_config.txArbitrationStartDelay (C var), 338
drivers_MCX_MCXA_MCXA366._flexcan_config.wakeupSrc (C var), 337
drivers_MCX_MCXA_MCXA366._flexcan_edma_handle (C struct), 353
drivers_MCX_MCXA_MCXA366._flexcan_edma_handle.callback (C var), 353
drivers_MCX_MCXA_MCXA366._flexcan_edma_handle.framefd (C var), 353
drivers_MCX_MCXA_MCXA366._flexcan_edma_handle.frameNum (C var), 353
drivers_MCX_MCXA_MCXA366._flexcan_edma_handle.rxFifoEdmaHandle (C var), 353
drivers_MCX_MCXA_MCXA366._flexcan_edma_handle.rxFifoState (C var), 353
drivers_MCX_MCXA_MCXA366._flexcan_edma_handle.userData (C var), 353
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length (C enum), 321
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_1WordPerRead (C enumerator), 321
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_2WordPerRead (C enumerator), 321
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_3WordPerRead (C enumerator), 321
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_4WordPerRead (C enumerator), 321
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_5WordPerRead (C enumerator), 321
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_6WordPerRead (C enumerator), 321
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_7WordPerRead (C enumerator), 321
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_8WordPerRead (C enumerator), 321
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_9WordPerRead (C enumerator), 321
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_10WordPerRead (C enumerator), 321
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_11WordPerRead (C enumerator), 322
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_12WordPerRead

(*C enumerator*), 322
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_13WordPerRead (*C enumerator*), 322
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_14WordPerRead (*C enumerator*), 322
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_15WordPerRead (*C enumerator*), 322
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_16WordPerRead (*C enumerator*), 322
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_17WordPerRead (*C enumerator*), 322
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_18WordPerRead (*C enumerator*), 322
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_19WordPerRead (*C enumerator*), 322
drivers_MCX_MCXA_MCXA366._flexcan_efifo_dma_per_read_length.kFLEXCAN_20WordPerRead (*C enumerator*), 322
drivers_MCX_MCXA_MCXA366._flexcan_endianness (*C enum*), 318
drivers_MCX_MCXA_MCXA366._flexcan_endianness.kFLEXCAN_bigEndian (*C enumerator*), 318
drivers_MCX_MCXA_MCXA366._flexcan_endianness.kFLEXCAN_littleEndian (*C enumerator*), 318
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_config (*C struct*), 341
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_config.dmaPerReadLength (*C var*), 342
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_config.extendIdFilterNum (*C var*), 342
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_config.fifoWatermark (*C var*), 342
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_config.idFilterPairNum (*C var*), 342
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_config.idFilterTable (*C var*), 341
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_config.priority (*C var*), 342
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_ext_id_filter (*C struct*), 341
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_ext_id_filter.filterType (*C var*), 341
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_ext_id_filter.rtr1 (*C var*), 341
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_ext_id_filter.rtr2 (*C var*), 341
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_ext_id_filter.std1 (*C var*), 341
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_ext_id_filter.std2 (*C var*), 341
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_std_id_filter (*C struct*), 340
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_std_id_filter.filterType (*C var*), 340
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_std_id_filter.rtr1 (*C var*), 341
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_std_id_filter.rtr2 (*C var*), 341
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_std_id_filter.std1 (*C var*), 341
drivers_MCX_MCXA_MCXA366._flexcan_enhanced_rx_fifo_std_id_filter.std2 (*C var*), 341
drivers_MCX_MCXA_MCXA366._flexcan_error_flags (*C enum*), 325
drivers_MCX_MCXA_MCXA366._flexcan_error_flags.kFLEXCAN_AckError (*C enumerator*), 326
drivers_MCX_MCXA_MCXA366._flexcan_error_flags.kFLEXCAN_Bit0Error (*C enumerator*), 326
drivers_MCX_MCXA_MCXA366._flexcan_error_flags.kFLEXCAN_Bit1Error (*C enumerator*), 326
drivers_MCX_MCXA_MCXA366._flexcan_error_flags.kFLEXCAN_CrcError (*C enumerator*), 326
drivers_MCX_MCXA_MCXA366._flexcan_error_flags.kFLEXCAN_FDBit0Error (*C enumerator*), 326
drivers_MCX_MCXA_MCXA366._flexcan_error_flags.kFLEXCAN_FDBit1Error (*C enumerator*), 326
drivers_MCX_MCXA_MCXA366._flexcan_error_flags.kFLEXCAN_FDCrcError (*C enumerator*), 326
drivers_MCX_MCXA_MCXA366._flexcan_error_flags.kFLEXCAN_FDFormError (*C enumerator*), 326
drivers_MCX_MCXA_MCXA366._flexcan_error_flags.kFLEXCAN_FDStuffingError (*C enumerator*), 326
drivers_MCX_MCXA_MCXA366._flexcan_error_flags.kFLEXCAN_FormError (*C enumerator*),

326
drivers_MCX_MCXA_MCXA366._flexcan_error_flags.kFLEXCAN_RxErrorWarningFlag (*C enumerator*), 326
drivers_MCX_MCXA_MCXA366._flexcan_error_flags.kFLEXCAN_StuffingError (*C enumerator*), 326
drivers_MCX_MCXA_MCXA366._flexcan_error_flags.kFLEXCAN_TxErrorWarningFlag (*C enumerator*), 326
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame (*C struct*), 336
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed32___ (*C struct*), 345
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed32___.brs (*C var*), 346
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed32___.edl (*C var*), 346
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed32___.esi (*C var*), 346
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed32___.format (*C var*), 346
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed32___.length (*C var*), 346
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed32___.srr (*C var*), 346
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed32___.timestamp (*C var*), 345
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed32___.type (*C var*), 346
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed34___ (*C struct*), 346
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed34___.___pad0___ (*C var*), 346
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed34___.id (*C var*), 346
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed36___ (*C union*), 346
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed36___.___unnamed38___ (*C struct*), 346
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed36___.___unnamed38___.dataWord (*C var*), 347
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed36___.___unnamed40___ (*C struct*), 347
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed36___.___unnamed40___.dataByte0 (*C var*), 347
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed36___.___unnamed40___.dataByte1 (*C var*), 347
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed36___.___unnamed40___.dataByte2 (*C var*), 347
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed36___.___unnamed40___.dataByte3 (*C var*), 347
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed36___.___unnamed40___.dataByte4 (*C var*), 347
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed36___.___unnamed40___.dataByte5 (*C var*), 347
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed36___.___unnamed40___.dataByte6 (*C var*), 347
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.___unnamed36___.___unnamed40___.dataByte7 (*C var*), 347
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame_length (*C enum*), 320
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame_length.kFLEXCAN_0BperFrame (*C enumerator*), 320
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame_length.kFLEXCAN_1BperFrame (*C enumerator*), 320
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame_length.kFLEXCAN_2BperFrame (*C enumerator*), 320
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame_length.kFLEXCAN_3BperFrame (*C enumerator*), 320
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame_length.kFLEXCAN_4BperFrame (*C enumerator*), 320
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame_length.kFLEXCAN_5BperFrame (*C enumerator*), 320
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame_length.kFLEXCAN_6BperFrame (*C enumerator*), 320

drivers_MCX_MCXA_MCXA366._flexcan_fd_frame_length.kFLEXCAN_7BperFrame (*C enumerator*), 320
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame_length.kFLEXCAN_8BperFrame (*C enumerator*), 320
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame_length.kFLEXCAN_12BperFrame (*C enumerator*), 320
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame_length.kFLEXCAN_16BperFrame (*C enumerator*), 320
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame_length.kFLEXCAN_20BperFrame (*C enumerator*), 321
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame_length.kFLEXCAN_24BperFrame (*C enumerator*), 321
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame_length.kFLEXCAN_32BperFrame (*C enumerator*), 321
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame_length.kFLEXCAN_48BperFrame (*C enumerator*), 321
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame_length.kFLEXCAN_64BperFrame (*C enumerator*), 321
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.hrtimestamp (*C var*), 336
drivers_MCX_MCXA_MCXA366._flexcan_fd_frame.idhit (*C var*), 336
drivers_MCX_MCXA_MCXA366._flexcan_fifo_transfer (*C struct*), 342
drivers_MCX_MCXA_MCXA366._flexcan_fifo_transfer.frame (*C var*), 342
drivers_MCX_MCXA_MCXA366._flexcan_fifo_transfer.framefd (*C var*), 342
drivers_MCX_MCXA_MCXA366._flexcan_fifo_transfer.frameNum (*C var*), 343
drivers_MCX_MCXA_MCXA366._flexcan_flags (*C enum*), 324
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_AllMemoryErrorFlag (*C enumerator*), 325
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_AllMemoryErrorIntFlag (*C enumerator*), 325
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_BusoffDoneIntFlag (*C enumerator*), 324
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_BusOffIntFlag (*C enumerator*), 324
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_CorrectableErrorIntFlag (*C enumerator*), 325
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_CorrectableErrorOverrunFlag (*C enumerator*), 325
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_ErrorFlag (*C enumerator*), 324
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_ErrorIntFlag (*C enumerator*), 324
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_ErrorOverrunFlag (*C enumerator*), 324
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_ERxFifoDataAvlIntFlag (*C enumerator*), 325
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_ERxFifoEmptyFlag (*C enumerator*), 325
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_ERxFifoFullFlag (*C enumerator*), 325
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_ERxFifoOverflowIntFlag (*C enumerator*), 325
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_ERxFifoUnderflowIntFlag (*C enumerator*), 325
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_ERxFifoWatermarkIntFlag (*C enumerator*), 325
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_FaultConfinementFlag (*C enumerator*), 324
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_FDErrorIntFlag (*C enumerator*), 324
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_FlexCanAccessNonCorrectableErrorIntFlag (*C enumerator*), 325
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_FlexCanAccessNonCorrectableErrorOverrunFlag (*C enumerator*), 325

drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_HostAccessNonCorrectableErrorIntFlag (*C enumerator*), 325
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_HostAccessNonCorrectableErrorOverrunFlag (*C enumerator*), 325
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_IdleFlag (*C enumerator*), 324
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_PNMatchIntFlag (*C enumerator*), 325
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_PNTimeoutIntFlag (*C enumerator*), 325
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_ReceivingFlag (*C enumerator*), 324
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_RxWarningIntFlag (*C enumerator*), 324
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_SynchFlag (*C enumerator*), 324
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_TransmittingFlag (*C enumerator*), 324
drivers_MCX_MCXA_MCXA366._flexcan_flags.kFLEXCAN_TxWarningIntFlag (*C enumerator*), 324
drivers_MCX_MCXA_MCXA366._flexcan_frame (*C struct*), 336
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed22___ (*C struct*), 344
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed22___.___pad0___ (*C var*), 344
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed22___.format (*C var*), 344
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed22___.idhit (*C var*), 344
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed22___.length (*C var*), 344
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed22___.timestamp (*C var*), 344
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed22___.type (*C var*), 344
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed24___ (*C struct*), 344
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed24___.___pad0___ (*C var*), 344
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed24___.id (*C var*), 344
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed26___ (*C union*), 344
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed26___.___unnamed28___ (*C struct*), 345
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed26___.___unnamed28___.dataWord0 (*C var*), 345
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed26___.___unnamed28___.dataWord1 (*C var*), 345
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed26___.___unnamed30___ (*C struct*), 345
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed26___.___unnamed30___.dataByte0 (*C var*), 345
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed26___.___unnamed30___.dataByte1 (*C var*), 345
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed26___.___unnamed30___.dataByte2 (*C var*), 345
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed26___.___unnamed30___.dataByte3 (*C var*), 345
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed26___.___unnamed30___.dataByte4 (*C var*), 345
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed26___.___unnamed30___.dataByte5 (*C var*), 345
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed26___.___unnamed30___.dataByte6 (*C var*), 345
drivers_MCX_MCXA_MCXA366._flexcan_frame.___unnamed26___.___unnamed30___.dataByte7 (*C var*), 345
drivers_MCX_MCXA_MCXA366._flexcan_frame_format (*C enum*), 317
drivers_MCX_MCXA_MCXA366._flexcan_frame_format.kFLEXCAN_FrameFormatExtend (*C enumerator*), 317
drivers_MCX_MCXA_MCXA366._flexcan_frame_format.kFLEXCAN_FrameFormatStandard (*C enumerator*), 317

drivers_MCX_MCXA_MCXA366._flexcan_frame_type (*C enum*), 317
drivers_MCX_MCXA_MCXA366._flexcan_frame_type.kFLEXCAN_FrameTypeData (*C enumerator*), 317
drivers_MCX_MCXA_MCXA366._flexcan_frame_type.kFLEXCAN_FrameTypeRemote (*C enumerator*), 317
drivers_MCX_MCXA_MCXA366._flexcan_handle (*C struct*), 343
drivers_MCX_MCXA_MCXA366._flexcan_handle.callback (*C var*), 343
drivers_MCX_MCXA_MCXA366._flexcan_handle.mbFDFrameBuf (*C var*), 343
drivers_MCX_MCXA_MCXA366._flexcan_handle.mbFrameBuf (*C var*), 343
drivers_MCX_MCXA_MCXA366._flexcan_handle.mbState (*C var*), 343
drivers_MCX_MCXA_MCXA366._flexcan_handle.rxFifoFDFrameBuf (*C var*), 343
drivers_MCX_MCXA_MCXA366._flexcan_handle.rxFifoFrameBuf (*C var*), 343
drivers_MCX_MCXA_MCXA366._flexcan_handle.rxFifoFrameNum (*C var*), 343
drivers_MCX_MCXA_MCXA366._flexcan_handle.rxFifoState (*C var*), 343
drivers_MCX_MCXA_MCXA366._flexcan_handle.rxFifoTransferTotalNum (*C var*), 343
drivers_MCX_MCXA_MCXA366._flexcan_handle.timestamp (*C var*), 343
drivers_MCX_MCXA_MCXA366._flexcan_handle.userData (*C var*), 343
drivers_MCX_MCXA_MCXA366._flexcan_interrupt_enable (*C enum*), 322
drivers_MCX_MCXA_MCXA366._flexcan_interrupt_enable.kFLEXCAN_BusOffInterruptEnable (*C enumerator*), 323
drivers_MCX_MCXA_MCXA366._flexcan_interrupt_enable.kFLEXCAN_ErrorInterruptEnable (*C enumerator*), 323
drivers_MCX_MCXA_MCXA366._flexcan_interrupt_enable.kFLEXCAN_ERxFifoDataAvlInterruptEnable (*C enumerator*), 323
drivers_MCX_MCXA_MCXA366._flexcan_interrupt_enable.kFLEXCAN_ERxFifoOverflowInterruptEnable (*C enumerator*), 323
drivers_MCX_MCXA_MCXA366._flexcan_interrupt_enable.kFLEXCAN_ERxFifoUnderflowInterruptEnable (*C enumerator*), 323
drivers_MCX_MCXA_MCXA366._flexcan_interrupt_enable.kFLEXCAN_ERxFifoWatermarkInterruptEnable (*C enumerator*), 323
drivers_MCX_MCXA_MCXA366._flexcan_interrupt_enable.kFLEXCAN_FDErrorInterruptEnable (*C enumerator*), 323
drivers_MCX_MCXA_MCXA366._flexcan_interrupt_enable.kFLEXCAN_FlexCanAccessNCErrorInterruptEnable (*C enumerator*), 323
drivers_MCX_MCXA_MCXA366._flexcan_interrupt_enable.kFLEXCAN_HostAccessNCErrorInterruptEnable (*C enumerator*), 323
drivers_MCX_MCXA_MCXA366._flexcan_interrupt_enable.kFLEXCAN_HostOrFlexCanCErrorInterruptEnable (*C enumerator*), 323
drivers_MCX_MCXA_MCXA366._flexcan_interrupt_enable.kFLEXCAN_PNMatchWakeUpInterruptEnable (*C enumerator*), 323
drivers_MCX_MCXA_MCXA366._flexcan_interrupt_enable.kFLEXCAN_PNTimeoutWakeUpInterruptEnable (*C enumerator*), 323
drivers_MCX_MCXA_MCXA366._flexcan_interrupt_enable.kFLEXCAN_RxWarningInterruptEnable (*C enumerator*), 323
drivers_MCX_MCXA_MCXA366._flexcan_interrupt_enable.kFLEXCAN_TxWarningInterruptEnable (*C enumerator*), 323
drivers_MCX_MCXA_MCXA366._flexcan_mb_size (*C enum*), 319
drivers_MCX_MCXA_MCXA366._flexcan_mb_size.kFLEXCAN_8BperMB (*C enumerator*), 319
drivers_MCX_MCXA_MCXA366._flexcan_mb_size.kFLEXCAN_16BperMB (*C enumerator*), 319
drivers_MCX_MCXA_MCXA366._flexcan_mb_size.kFLEXCAN_32BperMB (*C enumerator*), 320
drivers_MCX_MCXA_MCXA366._flexcan_mb_size.kFLEXCAN_64BperMB (*C enumerator*), 320
drivers_MCX_MCXA_MCXA366._flexcan_MB_timestamp_base (*C enum*), 318
drivers_MCX_MCXA_MCXA366._flexcan_MB_timestamp_base.kFLEXCAN_CANTimer (*C enumerator*), 318
drivers_MCX_MCXA_MCXA366._flexcan_MB_timestamp_base.kFLEXCAN_Lower16bitsHRTimer (*C enumerator*), 319
drivers_MCX_MCXA_MCXA366._flexcan_MB_timestamp_base.kFLEXCAN_Upper16bitsHRTimer (*C enumerator*), 319

drivers_MCX_MCXA_MCXA366._flexcan_mb_transfer (*C struct*), 342
drivers_MCX_MCXA_MCXA366._flexcan_mb_transfer.frame (*C var*), 342
drivers_MCX_MCXA_MCXA366._flexcan_mb_transfer.mbIdx (*C var*), 342
drivers_MCX_MCXA_MCXA366._flexcan_memory_access_type (*C enum*), 327
drivers_MCX_MCXA_MCXA366._flexcan_memory_access_type.kFLEXCAN_MoveInAccess (*C enumerator*), 327
drivers_MCX_MCXA_MCXA366._flexcan_memory_access_type.kFLEXCAN_MoveOutFlexCanAccess (*C enumerator*), 327
drivers_MCX_MCXA_MCXA366._flexcan_memory_access_type.kFLEXCAN_MoveOutHostAccess (*C enumerator*), 327
drivers_MCX_MCXA_MCXA366._flexcan_memory_access_type.kFLEXCAN_RxMatchingAccess (*C enumerator*), 327
drivers_MCX_MCXA_MCXA366._flexcan_memory_access_type.kFLEXCAN_TxArbitrationAccess (*C enumerator*), 327
drivers_MCX_MCXA_MCXA366._flexcan_memory_error_report_status (*C struct*), 335
drivers_MCX_MCXA_MCXA366._flexcan_memory_error_report_status.accessAddress (*C var*), 335
drivers_MCX_MCXA_MCXA366._flexcan_memory_error_report_status.accessType (*C var*), 335
drivers_MCX_MCXA_MCXA366._flexcan_memory_error_report_status.byteStatus (*C struct*), 343
drivers_MCX_MCXA_MCXA366._flexcan_memory_error_report_status.byteStatus.byteIsRead (*C var*), 344
drivers_MCX_MCXA_MCXA366._flexcan_memory_error_report_status.errorData (*C var*), 335
drivers_MCX_MCXA_MCXA366._flexcan_memory_error_report_status.errorType (*C var*), 335
drivers_MCX_MCXA_MCXA366._flexcan_memory_error_type (*C enum*), 327
drivers_MCX_MCXA_MCXA366._flexcan_memory_error_type.kFLEXCAN_CorrectableError (*C enumerator*), 327
drivers_MCX_MCXA_MCXA366._flexcan_memory_error_type.kFLEXCAN_NonCorrectableError (*C enumerator*), 327
drivers_MCX_MCXA_MCXA366._flexcan_pn_config (*C struct*), 339
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed48___ (*C union*), 348
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed48___.___unnamed52___ (*C struct*), 348
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed48___.___unnamed52___.lowerWord0 (*C var*), 348
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed48___.___unnamed52___.lowerWord1 (*C var*), 348
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed48___.___unnamed54___ (*C struct*), 348
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed48___.___unnamed54___.lowerByte0 (*C var*), 349
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed48___.___unnamed54___.lowerByte1 (*C var*), 349
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed48___.___unnamed54___.lowerByte2 (*C var*), 349
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed48___.___unnamed54___.lowerByte3 (*C var*), 349
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed48___.___unnamed54___.lowerByte4 (*C var*), 349
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed48___.___unnamed54___.lowerByte5 (*C var*), 349
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed48___.___unnamed54___.lowerByte6 (*C var*), 349
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed48___.___unnamed54___.lowerByte7 (*C var*), 349
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed50___ (*C union*), 349
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed50___.___unnamed56___ (*C struct*), 349
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed50___.___unnamed56___.upperWord0 (*C var*), 349

drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed50___.___unnamed56___.upperWord1 (*C var*), 349
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed50___.___unnamed58___ (*C struct*), 350
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed50___.___unnamed58___.upperByte0 (*C var*), 350
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed50___.___unnamed58___.upperByte1 (*C var*), 350
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed50___.___unnamed58___.upperByte2 (*C var*), 350
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed50___.___unnamed58___.upperByte3 (*C var*), 350
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed50___.___unnamed58___.upperByte4 (*C var*), 350
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed50___.___unnamed58___.upperByte5 (*C var*), 350
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed50___.___unnamed58___.upperByte6 (*C var*), 350
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.___unnamed50___.___unnamed58___.upperByte7 (*C var*), 350
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.dataMatchMode (*C var*), 340
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.enableMatch (*C var*), 339
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.enableTimeout (*C var*), 339
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.idLower (*C var*), 340
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.idMatchMode (*C var*), 339
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.idUpper (*C var*), 340
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.lengthLower (*C var*), 340
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.lengthUpper (*C var*), 340
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.matchNum (*C var*), 339
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.matchSrc (*C var*), 339
drivers_MCX_MCXA_MCXA366._flexcan_pn_config.timeoutValue (*C var*), 339
drivers_MCX_MCXA_MCXA366._flexcan_pn_match_mode (*C enum*), 329
drivers_MCX_MCXA_MCXA366._flexcan_pn_match_mode.kFLEXCAN_PNMatModeEqual (*C enumerator*), 329
drivers_MCX_MCXA_MCXA366._flexcan_pn_match_mode.kFLEXCAN_PNMatModeGreater (*C enumerator*), 329
drivers_MCX_MCXA_MCXA366._flexcan_pn_match_mode.kFLEXCAN_PNMatModeRange (*C enumerator*), 329
drivers_MCX_MCXA_MCXA366._flexcan_pn_match_mode.kFLEXCAN_PNMatModeSmaller (*C enumerator*), 329
drivers_MCX_MCXA_MCXA366._flexcan_pn_match_source (*C enum*), 329
drivers_MCX_MCXA_MCXA366._flexcan_pn_match_source.kFLEXCAN_PNMatSrcID (*C enumerator*), 329
drivers_MCX_MCXA_MCXA366._flexcan_pn_match_source.kFLEXCAN_PNMatSrcIDAndData (*C enumerator*), 329
drivers_MCX_MCXA_MCXA366._flexcan_rx_fifo_config (*C struct*), 340
drivers_MCX_MCXA_MCXA366._flexcan_rx_fifo_config.idFilterNum (*C var*), 340
drivers_MCX_MCXA_MCXA366._flexcan_rx_fifo_config.idFilterTable (*C var*), 340
drivers_MCX_MCXA_MCXA366._flexcan_rx_fifo_config.idFilterType (*C var*), 340
drivers_MCX_MCXA_MCXA366._flexcan_rx_fifo_config.priority (*C var*), 340
drivers_MCX_MCXA_MCXA366._flexcan_rx_fifo_filter_type (*C enum*), 319
drivers_MCX_MCXA_MCXA366._flexcan_rx_fifo_filter_type.kFLEXCAN_RxFifoFilterTypeA (*C enumerator*), 319
drivers_MCX_MCXA_MCXA366._flexcan_rx_fifo_filter_type.kFLEXCAN_RxFifoFilterTypeB (*C enumerator*), 319
drivers_MCX_MCXA_MCXA366._flexcan_rx_fifo_filter_type.kFLEXCAN_RxFifoFilterTypeC (*C enumerator*), 319
drivers_MCX_MCXA_MCXA366._flexcan_rx_fifo_filter_type.kFLEXCAN_RxFifoFilterTypeD (*C*

enumerator), 319
drivers_MCX_MCXA_MCXA366._flexcan_rx_fifo_priority (*C enum*), 322
drivers_MCX_MCXA_MCXA366._flexcan_rx_fifo_priority.kFLEXCAN_RxFifoPrioHigh (*C enumerator*), 322
drivers_MCX_MCXA_MCXA366._flexcan_rx_fifo_priority.kFLEXCAN_RxFifoPrioLow (*C enumerator*), 322
drivers_MCX_MCXA_MCXA366._flexcan_rx_mb_config (*C struct*), 339
drivers_MCX_MCXA_MCXA366._flexcan_rx_mb_config.format (*C var*), 339
drivers_MCX_MCXA_MCXA366._flexcan_rx_mb_config.id (*C var*), 339
drivers_MCX_MCXA_MCXA366._flexcan_rx_mb_config.type (*C var*), 339
drivers_MCX_MCXA_MCXA366._flexcan_timing_config (*C struct*), 336
drivers_MCX_MCXA_MCXA366._flexcan_timing_config.fphaseSeg1 (*C var*), 337
drivers_MCX_MCXA_MCXA366._flexcan_timing_config.fphaseSeg2 (*C var*), 337
drivers_MCX_MCXA_MCXA366._flexcan_timing_config.fpreDivider (*C var*), 336
drivers_MCX_MCXA_MCXA366._flexcan_timing_config.fpropSeg (*C var*), 337
drivers_MCX_MCXA_MCXA366._flexcan_timing_config.frJumpwidth (*C var*), 337
drivers_MCX_MCXA_MCXA366._flexcan_timing_config.phaseSeg1 (*C var*), 336
drivers_MCX_MCXA_MCXA366._flexcan_timing_config.phaseSeg2 (*C var*), 336
drivers_MCX_MCXA_MCXA366._flexcan_timing_config.preDivider (*C var*), 336
drivers_MCX_MCXA_MCXA366._flexcan_timing_config.propSeg (*C var*), 336
drivers_MCX_MCXA_MCXA366._flexcan_timing_config.rJumpwidth (*C var*), 336
drivers_MCX_MCXA_MCXA366._flexcan_wake_up_source (*C enum*), 318
drivers_MCX_MCXA_MCXA366._flexcan_wake_up_source.kFLEXCAN_WakeupSrcFiltered (*C enumerator*), 318
drivers_MCX_MCXA_MCXA366._flexcan_wake_up_source.kFLEXCAN_WakeupSrcUnfiltered (*C enumerator*), 318
drivers_MCX_MCXA_MCXA366._flexio_a_format_baud_rate_bps (*C enum*), 354
drivers_MCX_MCXA_MCXA366._flexio_a_format_baud_rate_bps.kFLEXIO_A_FORMAT_2_5MHZ (*C enumerator*), 354
drivers_MCX_MCXA_MCXA366._flexio_a_format_baud_rate_bps.kFLEXIO_A_FORMAT_4MHZ (*C enumerator*), 354
drivers_MCX_MCXA_MCXA366._flexio_a_format_baud_rate_bps.kFLEXIO_A_FORMAT_6_67MHZ (*C enumerator*), 355
drivers_MCX_MCXA_MCXA366._flexio_a_format_baud_rate_bps.kFLEXIO_A_FORMAT_8MHZ (*C enumerator*), 355
drivers_MCX_MCXA_MCXA366._flexio_a_format_baud_rate_bps.kFLEXIO_A_FORMAT_16MHZ (*C enumerator*), 355
drivers_MCX_MCXA_MCXA366._flexio_a_format_config (*C struct*), 369
drivers_MCX_MCXA_MCXA366._flexio_a_format_encoder_status (*C enum*), 354
drivers_MCX_MCXA_MCXA366._flexio_a_format_encoder_status.kFLEXIO_A_FORMAT_ES_Anyone (*C enumerator*), 354
drivers_MCX_MCXA_MCXA366._flexio_a_format_encoder_status.kFLEXIO_A_FORMAT_ES_Batt (*C enumerator*), 354
drivers_MCX_MCXA_MCXA366._flexio_a_format_encoder_status.kFLEXIO_A_FORMAT_ES_Busy_MemBusy (*C enumerator*), 354
drivers_MCX_MCXA_MCXA366._flexio_a_format_encoder_status.kFLEXIO_A_FORMAT_ES_FrameErr (*C enumerator*), 354
drivers_MCX_MCXA_MCXA366._flexio_a_format_encoder_status.kFLEXIO_A_FORMAT_ES_NoErr (*C enumerator*), 354
drivers_MCX_MCXA_MCXA366._flexio_a_format_encoder_status.kFLEXIO_A_FORMAT_ES_OvSpd_MemErr (*C enumerator*), 354
drivers_MCX_MCXA_MCXA366._flexio_a_format_encoder_status.kFLEXIO_A_FORMAT_ES_STErr_PSErr_M (*C enumerator*), 354
drivers_MCX_MCXA_MCXA366._flexio_a_format_handle (*C struct*), 369
drivers_MCX_MCXA_MCXA366._flexio_a_format_interrupt_enable (*C enum*), 355
drivers_MCX_MCXA_MCXA366._flexio_a_format_interrupt_enable.kFLEXIO_A_FORMAT_RxDataRegFullInte (*C enumerator*), 355
drivers_MCX_MCXA_MCXA366._flexio_a_format_interrupt_enable.kFLEXIO_A_FORMAT_TxDataRegEmptyI

(*C enumerator*), 355
drivers_MCX_MCXA_MCXA366._flexio_a_format_status_flags (*C enum*), 355
drivers_MCX_MCXA_MCXA366._flexio_a_format_status_flags.kFLEXIO_A_FORMAT_RxDataRegFullFlag (*C enumerator*), 355
drivers_MCX_MCXA_MCXA366._flexio_a_format_status_flags.kFLEXIO_A_FORMAT_RxOverRunFlag (*C enumerator*), 355
drivers_MCX_MCXA_MCXA366._flexio_a_format_status_flags.kFLEXIO_A_FORMAT_TxDataRegEmptyFlag (*C enumerator*), 355
drivers_MCX_MCXA_MCXA366._flexio_a_format_transfer (*C struct*), 369
drivers_MCX_MCXA_MCXA366._flexio_a_format_transfer.___unnamed84___ (*C union*), 369
drivers_MCX_MCXA_MCXA366._flexio_a_format_transfer.___unnamed84___.data (*C var*), 369
drivers_MCX_MCXA_MCXA366._flexio_a_format_transfer.___unnamed84___.rxData (*C var*), 369
drivers_MCX_MCXA_MCXA366._flexio_a_format_transfer.___unnamed84___.txData (*C var*), 369
drivers_MCX_MCXA_MCXA366._flexio_a_format_type (*C struct*), 369
drivers_MCX_MCXA_MCXA366._flexio_a_format_user_modes (*C enum*), 355
drivers_MCX_MCXA_MCXA366._flexio_a_format_user_modes.kFLEXIO_A_FORMAT_USERMODE_ONESHO (*C enumerator*), 355
drivers_MCX_MCXA_MCXA366._flexio_a_format_user_modes.kFLEXIO_A_FORMAT_USERMODE_SYNC (*C enumerator*), 355
drivers_MCX_MCXA_MCXA366._flexio_camera_config (*C struct*), 372
drivers_MCX_MCXA_MCXA366._flexio_camera_config.enablecamera (*C var*), 372
drivers_MCX_MCXA_MCXA366._flexio_camera_config.enableFastAccess (*C var*), 372
drivers_MCX_MCXA_MCXA366._flexio_camera_config.enableInDebug (*C var*), 372
drivers_MCX_MCXA_MCXA366._flexio_camera_config.enableInDoze (*C var*), 372
drivers_MCX_MCXA_MCXA366._flexio_camera_status_flags (*C enum*), 371
drivers_MCX_MCXA_MCXA366._flexio_camera_status_flags.kFLEXIO_CAMERA_RxDataRegFullFlag (*C enumerator*), 371
drivers_MCX_MCXA_MCXA366._flexio_camera_status_flags.kFLEXIO_CAMERA_RxErrorFlag (*C enumerator*), 371
drivers_MCX_MCXA_MCXA366._flexio_camera_transfer (*C struct*), 373
drivers_MCX_MCXA_MCXA366._flexio_camera_transfer.dataAddress (*C var*), 373
drivers_MCX_MCXA_MCXA366._flexio_camera_transfer.dataNum (*C var*), 373
drivers_MCX_MCXA_MCXA366._flexio_camera_type (*C struct*), 372
drivers_MCX_MCXA_MCXA366._flexio_camera_type.datPinStartIdx (*C var*), 372
drivers_MCX_MCXA_MCXA366._flexio_camera_type.flexioBase (*C var*), 372
drivers_MCX_MCXA_MCXA366._flexio_camera_type.hrefPinIdx (*C var*), 372
drivers_MCX_MCXA_MCXA366._flexio_camera_type.pclkPinIdx (*C var*), 372
drivers_MCX_MCXA_MCXA366._flexio_camera_type.shifterCount (*C var*), 372
drivers_MCX_MCXA_MCXA366._flexio_camera_type.shifterStartIdx (*C var*), 372
drivers_MCX_MCXA_MCXA366._flexio_camera_type.timerIdx (*C var*), 372
drivers_MCX_MCXA_MCXA366._flexio_config_ (*C struct*), 390
drivers_MCX_MCXA_MCXA366._flexio_config_.enableFastAccess (*C var*), 390
drivers_MCX_MCXA_MCXA366._flexio_config_.enableFlexio (*C var*), 390
drivers_MCX_MCXA_MCXA366._flexio_config_.enableInDebug (*C var*), 390
drivers_MCX_MCXA_MCXA366._flexio_config_.enableInDoze (*C var*), 390
drivers_MCX_MCXA_MCXA366._flexio_gpio_config (*C struct*), 392
drivers_MCX_MCXA_MCXA366._flexio_gpio_config.inputConfig (*C var*), 393
drivers_MCX_MCXA_MCXA366._flexio_gpio_config.outputLogic (*C var*), 393
drivers_MCX_MCXA_MCXA366._flexio_gpio_config.pinDirection (*C var*), 393
drivers_MCX_MCXA_MCXA366._flexio_gpio_direction (*C enum*), 387
drivers_MCX_MCXA_MCXA366._flexio_gpio_direction.kFLEXIO_DigitalInput (*C enumerator*), 387
drivers_MCX_MCXA_MCXA366._flexio_gpio_direction.kFLEXIO_DigitalOutput (*C enumerator*), 387
drivers_MCX_MCXA_MCXA366._flexio_i2c_direction (*C enum*), 413
drivers_MCX_MCXA_MCXA366._flexio_i2c_direction.kFLEXIO_I2C_Read (*C enumerator*), 413
drivers_MCX_MCXA_MCXA366._flexio_i2c_direction.kFLEXIO_I2C_Write (*C enumerator*), 413
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_config (*C struct*), 414

drivers_MCX_MCXA_MCXA366._flexio_i2c_master_config.baudRate_Bps (*C var*), 414
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_config.enableFastAccess (*C var*), 414
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_config.enableInDebug (*C var*), 414
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_config.enableInDoze (*C var*), 414
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_config.enableMaster (*C var*), 414
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_handle (*C struct*), 415
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_handle.completionCallback (*C var*), 415
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_handle.needRestart (*C var*), 415
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_handle.state (*C var*), 415
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_handle.transfer (*C var*), 415
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_handle.transferSize (*C var*), 415
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_handle.userData (*C var*), 415
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_interrupt (*C enum*), 412
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_interrupt.kFLEXIO_I2C_RxFullInterruptEnable (*C enumerator*), 412
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_interrupt.kFLEXIO_I2C_TxEmptyInterruptEnable (*C enumerator*), 412
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_status_flags (*C enum*), 412
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_status_flags.kFLEXIO_I2C_ReceiveNakFlag (*C enumerator*), 413
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_status_flags.kFLEXIO_I2C_RxFullFlag (*C enumerator*), 413
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_status_flags.kFLEXIO_I2C_TxEmptyFlag (*C enumerator*), 413
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_transfer (*C struct*), 414
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_transfer.data (*C var*), 415
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_transfer.dataSize (*C var*), 415
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_transfer.direction (*C var*), 415
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_transfer.flags (*C var*), 414
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_transfer.slaveAddress (*C var*), 415
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_transfer.subaddress (*C var*), 415
drivers_MCX_MCXA_MCXA366._flexio_i2c_master_transfer.subaddressSize (*C var*), 415
drivers_MCX_MCXA_MCXA366._flexio_i2c_type (*C struct*), 413
drivers_MCX_MCXA_MCXA366._flexio_i2c_type.baudrate (*C var*), 414
drivers_MCX_MCXA_MCXA366._flexio_i2c_type.flexioBase (*C var*), 414
drivers_MCX_MCXA_MCXA366._flexio_i2c_type.SCLPinIndex (*C var*), 414
drivers_MCX_MCXA_MCXA366._flexio_i2c_type.SDAPinIndex (*C var*), 414
drivers_MCX_MCXA_MCXA366._flexio_i2c_type.shifterIndex (*C var*), 414
drivers_MCX_MCXA_MCXA366._flexio_i2c_type.timerIndex (*C var*), 414
drivers_MCX_MCXA_MCXA366._flexio_i2s_config (*C struct*), 425
drivers_MCX_MCXA_MCXA366._flexio_i2s_config.bclkPinPolarity (*C var*), 426
drivers_MCX_MCXA_MCXA366._flexio_i2s_config.enableI2S (*C var*), 425
drivers_MCX_MCXA_MCXA366._flexio_i2s_config.fsPinPolarity (*C var*), 426
drivers_MCX_MCXA_MCXA366._flexio_i2s_config.masterSlave (*C var*), 425
drivers_MCX_MCXA_MCXA366._flexio_i2s_config.rxPinPolarity (*C var*), 426
drivers_MCX_MCXA_MCXA366._flexio_i2s_config.rxTimerPolarity (*C var*), 426
drivers_MCX_MCXA_MCXA366._flexio_i2s_config.txPinPolarity (*C var*), 425
drivers_MCX_MCXA_MCXA366._flexio_i2s_config.txTimerPolarity (*C var*), 426
drivers_MCX_MCXA_MCXA366._flexio_i2s_edma_handle (*C struct*), 396
drivers_MCX_MCXA_MCXA366._flexio_i2s_edma_handle.bytesPerFrame (*C var*), 396
drivers_MCX_MCXA_MCXA366._flexio_i2s_edma_handle.callback (*C var*), 396
drivers_MCX_MCXA_MCXA366._flexio_i2s_edma_handle.dmaHandle (*C var*), 396
drivers_MCX_MCXA_MCXA366._flexio_i2s_edma_handle.nbytes (*C var*), 396
drivers_MCX_MCXA_MCXA366._flexio_i2s_edma_handle.queue (*C var*), 396
drivers_MCX_MCXA_MCXA366._flexio_i2s_edma_handle.queueDriver (*C var*), 396
drivers_MCX_MCXA_MCXA366._flexio_i2s_edma_handle.queueUser (*C var*), 396
drivers_MCX_MCXA_MCXA366._flexio_i2s_edma_handle.state (*C var*), 396
drivers_MCX_MCXA_MCXA366._flexio_i2s_edma_handle.tcd (*C var*), 396

drivers_MCX_MCXA_MCXA366._flexio_i2s_edma_handle.transferSize (*C var*), 396
drivers_MCX_MCXA_MCXA366._flexio_i2s_edma_handle.userData (*C var*), 396
drivers_MCX_MCXA_MCXA366._flexio_i2s_format (*C struct*), 426
drivers_MCX_MCXA_MCXA366._flexio_i2s_format.bitWidth (*C var*), 426
drivers_MCX_MCXA_MCXA366._flexio_i2s_format.sampleRate_Hz (*C var*), 426
drivers_MCX_MCXA_MCXA366._flexio_i2s_handle (*C struct*), 426
drivers_MCX_MCXA_MCXA366._flexio_i2s_handle.bitWidth (*C var*), 427
drivers_MCX_MCXA_MCXA366._flexio_i2s_handle.callback (*C var*), 427
drivers_MCX_MCXA_MCXA366._flexio_i2s_handle.queue (*C var*), 427
drivers_MCX_MCXA_MCXA366._flexio_i2s_handle.queueDriver (*C var*), 427
drivers_MCX_MCXA_MCXA366._flexio_i2s_handle.queueUser (*C var*), 427
drivers_MCX_MCXA_MCXA366._flexio_i2s_handle.state (*C var*), 427
drivers_MCX_MCXA_MCXA366._flexio_i2s_handle.transferSize (*C var*), 427
drivers_MCX_MCXA_MCXA366._flexio_i2s_handle.userData (*C var*), 427
drivers_MCX_MCXA_MCXA366._flexio_i2s_master_slave (*C enum*), 422
drivers_MCX_MCXA_MCXA366._flexio_i2s_master_slave.kFLEXIO_I2S_Master (*C enumerator*), 422
drivers_MCX_MCXA_MCXA366._flexio_i2s_master_slave.kFLEXIO_I2S_Slave (*C enumerator*), 422
drivers_MCX_MCXA_MCXA366._flexio_i2s_sample_rate (*C enum*), 423
drivers_MCX_MCXA_MCXA366._flexio_i2s_sample_rate.kFLEXIO_I2S_SampleRate8KHz (*C enumerator*), 423
drivers_MCX_MCXA_MCXA366._flexio_i2s_sample_rate.kFLEXIO_I2S_SampleRate12KHz (*C enumerator*), 423
drivers_MCX_MCXA_MCXA366._flexio_i2s_sample_rate.kFLEXIO_I2S_SampleRate16KHz (*C enumerator*), 423
drivers_MCX_MCXA_MCXA366._flexio_i2s_sample_rate.kFLEXIO_I2S_SampleRate24KHz (*C enumerator*), 423
drivers_MCX_MCXA_MCXA366._flexio_i2s_sample_rate.kFLEXIO_I2S_SampleRate32KHz (*C enumerator*), 423
drivers_MCX_MCXA_MCXA366._flexio_i2s_sample_rate.kFLEXIO_I2S_SampleRate48KHz (*C enumerator*), 423
drivers_MCX_MCXA_MCXA366._flexio_i2s_sample_rate.kFLEXIO_I2S_SampleRate96KHz (*C enumerator*), 423
drivers_MCX_MCXA_MCXA366._flexio_i2s_sample_rate.kFLEXIO_I2S_SampleRate11025Hz (*C enumerator*), 423
drivers_MCX_MCXA_MCXA366._flexio_i2s_sample_rate.kFLEXIO_I2S_SampleRate22050Hz (*C enumerator*), 423
drivers_MCX_MCXA_MCXA366._flexio_i2s_sample_rate.kFLEXIO_I2S_SampleRate44100Hz (*C enumerator*), 423
drivers_MCX_MCXA_MCXA366._flexio_i2s_transfer (*C struct*), 426
drivers_MCX_MCXA_MCXA366._flexio_i2s_transfer.data (*C var*), 426
drivers_MCX_MCXA_MCXA366._flexio_i2s_transfer.dataSize (*C var*), 426
drivers_MCX_MCXA_MCXA366._flexio_i2s_type (*C struct*), 425
drivers_MCX_MCXA_MCXA366._flexio_i2s_type.bclkPinIndex (*C var*), 425
drivers_MCX_MCXA_MCXA366._flexio_i2s_type.bclkTimerIndex (*C var*), 425
drivers_MCX_MCXA_MCXA366._flexio_i2s_type.flexioBase (*C var*), 425
drivers_MCX_MCXA_MCXA366._flexio_i2s_type.fsPinIndex (*C var*), 425
drivers_MCX_MCXA_MCXA366._flexio_i2s_type.fsTimerIndex (*C var*), 425
drivers_MCX_MCXA_MCXA366._flexio_i2s_type.rxPinIndex (*C var*), 425
drivers_MCX_MCXA_MCXA366._flexio_i2s_type.rxShifterIndex (*C var*), 425
drivers_MCX_MCXA_MCXA366._flexio_i2s_type.txPinIndex (*C var*), 425
drivers_MCX_MCXA_MCXA366._flexio_i2s_type.txShifterIndex (*C var*), 425
drivers_MCX_MCXA_MCXA366._flexio_i2s_word_width (*C enum*), 424
drivers_MCX_MCXA_MCXA366._flexio_i2s_word_width.kFLEXIO_I2S_WordWidth8bits (*C enumerator*), 424
drivers_MCX_MCXA_MCXA366._flexio_i2s_word_width.kFLEXIO_I2S_WordWidth16bits (*C enumerator*), 424

drivers_MCX_MCXA_MCXA366._flexio_i2s_word_width.kFLEXIO_I2S_WordWidth24bits (*C enumerator*), 424
drivers_MCX_MCXA_MCXA366._flexio_i2s_word_width.kFLEXIO_I2S_WordWidth32bits (*C enumerator*), 424
drivers_MCX_MCXA_MCXA366._flexio_mculcd_bus (*C enum*), 435
drivers_MCX_MCXA_MCXA366._flexio_mculcd_bus.kFLEXIO_MCULCD_6800 (*C enumerator*), 436
drivers_MCX_MCXA_MCXA366._flexio_mculcd_bus.kFLEXIO_MCULCD_8080 (*C enumerator*), 435
drivers_MCX_MCXA_MCXA366._flexio_mculcd_config (*C struct*), 438
drivers_MCX_MCXA_MCXA366._flexio_mculcd_config.baudRate_Bps (*C var*), 439
drivers_MCX_MCXA_MCXA366._flexio_mculcd_config.enable (*C var*), 438
drivers_MCX_MCXA_MCXA366._flexio_mculcd_config.enableFastAccess (*C var*), 439
drivers_MCX_MCXA_MCXA366._flexio_mculcd_config.enableInDebug (*C var*), 439
drivers_MCX_MCXA_MCXA366._flexio_mculcd_config.enableInDoze (*C var*), 439
drivers_MCX_MCXA_MCXA366._flexio_mculcd_dma_enable (*C enum*), 436
drivers_MCX_MCXA_MCXA366._flexio_mculcd_dma_enable.kFLEXIO_MCULCD_RxDmaEnable (*C enumerator*), 436
drivers_MCX_MCXA_MCXA366._flexio_mculcd_dma_enable.kFLEXIO_MCULCD_TxDmaEnable (*C enumerator*), 436
drivers_MCX_MCXA_MCXA366._flexio_mculcd_edma_handle (*C struct*), 398
drivers_MCX_MCXA_MCXA366._flexio_mculcd_edma_handle.base (*C var*), 398
drivers_MCX_MCXA_MCXA366._flexio_mculcd_edma_handle.completionCallback (*C var*), 399
drivers_MCX_MCXA_MCXA366._flexio_mculcd_edma_handle.dataAddrOrSameValue (*C var*), 399
drivers_MCX_MCXA_MCXA366._flexio_mculcd_edma_handle.dataCount (*C var*), 399
drivers_MCX_MCXA_MCXA366._flexio_mculcd_edma_handle.minorLoopBytes (*C var*), 398
drivers_MCX_MCXA_MCXA366._flexio_mculcd_edma_handle.remainingCount (*C var*), 399
drivers_MCX_MCXA_MCXA366._flexio_mculcd_edma_handle.rxDmaHandle (*C var*), 399
drivers_MCX_MCXA_MCXA366._flexio_mculcd_edma_handle.rxEdmaModulo (*C var*), 399
drivers_MCX_MCXA_MCXA366._flexio_mculcd_edma_handle.rxShifterNum (*C var*), 398
drivers_MCX_MCXA_MCXA366._flexio_mculcd_edma_handle.state (*C var*), 399
drivers_MCX_MCXA_MCXA366._flexio_mculcd_edma_handle.txDmaHandle (*C var*), 399
drivers_MCX_MCXA_MCXA366._flexio_mculcd_edma_handle.txEdmaModulo (*C var*), 399
drivers_MCX_MCXA_MCXA366._flexio_mculcd_edma_handle.txShifterNum (*C var*), 398
drivers_MCX_MCXA_MCXA366._flexio_mculcd_edma_handle.userData (*C var*), 399
drivers_MCX_MCXA_MCXA366._flexio_mculcd_handle (*C struct*), 439
drivers_MCX_MCXA_MCXA366._flexio_mculcd_handle.completionCallback (*C var*), 440
drivers_MCX_MCXA_MCXA366._flexio_mculcd_handle.dataAddrOrSameValue (*C var*), 439
drivers_MCX_MCXA_MCXA366._flexio_mculcd_handle.dataCount (*C var*), 439
drivers_MCX_MCXA_MCXA366._flexio_mculcd_handle.remainingCount (*C var*), 440
drivers_MCX_MCXA_MCXA366._flexio_mculcd_handle.state (*C var*), 440
drivers_MCX_MCXA_MCXA366._flexio_mculcd_handle.userData (*C var*), 440
drivers_MCX_MCXA_MCXA366._flexio_mculcd_interrupt_enable (*C enum*), 436
drivers_MCX_MCXA_MCXA366._flexio_mculcd_interrupt_enable.kFLEXIO_MCULCD_RxFullInterruptEnable (*C enumerator*), 436
drivers_MCX_MCXA_MCXA366._flexio_mculcd_interrupt_enable.kFLEXIO_MCULCD_TxEmptyInterruptEnable (*C enumerator*), 436
drivers_MCX_MCXA_MCXA366._flexio_mculcd_pixel_format (*C enum*), 435
drivers_MCX_MCXA_MCXA366._flexio_mculcd_pixel_format.kFLEXIO_MCULCD_BGR565 (*C enumerator*), 435
drivers_MCX_MCXA_MCXA366._flexio_mculcd_pixel_format.kFLEXIO_MCULCD_BGR888 (*C enumerator*), 435
drivers_MCX_MCXA_MCXA366._flexio_mculcd_pixel_format.kFLEXIO_MCULCD_RGB565 (*C enumerator*), 435
drivers_MCX_MCXA_MCXA366._flexio_mculcd_pixel_format.kFLEXIO_MCULCD_RGB888 (*C enumerator*), 435
drivers_MCX_MCXA_MCXA366._flexio_mculcd_smartdma_config (*C struct*), 442
drivers_MCX_MCXA_MCXA366._flexio_mculcd_smartdma_config.inputPixelFormat (*C var*), 443

drivers_MCX_MCXA_MCXA366._flexio_mculcd_smartdma_config.outputPixelFormat (*C var*), 443
drivers_MCX_MCXA_MCXA366._flexio_mculcd_smartdma_handle (*C struct*), 442
drivers_MCX_MCXA_MCXA366._flexio_mculcd_smartdma_handle.base (*C var*), 442
drivers_MCX_MCXA_MCXA366._flexio_mculcd_smartdma_handle.blockingXferBuffer (*C var*), 442
drivers_MCX_MCXA_MCXA366._flexio_mculcd_smartdma_handle.completionCallback (*C var*), 442
drivers_MCX_MCXA_MCXA366._flexio_mculcd_smartdma_handle.dataAddrOrSameValue (*C var*), 442
drivers_MCX_MCXA_MCXA366._flexio_mculcd_smartdma_handle.dataCount (*C var*), 442
drivers_MCX_MCXA_MCXA366._flexio_mculcd_smartdma_handle.dataCountUsingEzh (*C var*), 442
drivers_MCX_MCXA_MCXA366._flexio_mculcd_smartdma_handle.needColorConvert (*C var*), 442
drivers_MCX_MCXA_MCXA366._flexio_mculcd_smartdma_handle.remainingCount (*C var*), 442
drivers_MCX_MCXA_MCXA366._flexio_mculcd_smartdma_handle.smartdmaApi (*C var*), 442
drivers_MCX_MCXA_MCXA366._flexio_mculcd_smartdma_handle.smartdmaParam (*C var*), 442
drivers_MCX_MCXA_MCXA366._flexio_mculcd_smartdma_handle.smartdmaStack (*C var*), 442
drivers_MCX_MCXA_MCXA366._flexio_mculcd_smartdma_handle.state (*C var*), 442
drivers_MCX_MCXA_MCXA366._flexio_mculcd_smartdma_handle.userData (*C var*), 442
drivers_MCX_MCXA_MCXA366._flexio_mculcd_status_flags (*C enum*), 436
drivers_MCX_MCXA_MCXA366._flexio_mculcd_status_flags.kFLEXIO_MCULCD_RxFullFlag (*C enumerator*), 436
drivers_MCX_MCXA_MCXA366._flexio_mculcd_status_flags.kFLEXIO_MCULCD_TxEmptyFlag (*C enumerator*), 436
drivers_MCX_MCXA_MCXA366._flexio_mculcd_transfer (*C struct*), 439
drivers_MCX_MCXA_MCXA366._flexio_mculcd_transfer_mode (*C enum*), 436
drivers_MCX_MCXA_MCXA366._flexio_mculcd_transfer_mode.kFLEXIO_MCULCD_ReadArray (*C enumerator*), 436
drivers_MCX_MCXA_MCXA366._flexio_mculcd_transfer_mode.kFLEXIO_MCULCD_WriteArray (*C enumerator*), 436
drivers_MCX_MCXA_MCXA366._flexio_mculcd_transfer_mode.kFLEXIO_MCULCD_WriteSameValue (*C enumerator*), 436
drivers_MCX_MCXA_MCXA366._flexio_mculcd_transfer.command (*C var*), 439
drivers_MCX_MCXA_MCXA366._flexio_mculcd_transfer.dataAddrOrSameValue (*C var*), 439
drivers_MCX_MCXA_MCXA366._flexio_mculcd_transfer.dataOnly (*C var*), 439
drivers_MCX_MCXA_MCXA366._flexio_mculcd_transfer.dataSize (*C var*), 439
drivers_MCX_MCXA_MCXA366._flexio_mculcd_transfer.mode (*C var*), 439
drivers_MCX_MCXA_MCXA366._flexio_mculcd_type (*C struct*), 437
drivers_MCX_MCXA_MCXA366._flexio_mculcd_type.busType (*C var*), 438
drivers_MCX_MCXA_MCXA366._flexio_mculcd_type.dataPinStartIndex (*C var*), 438
drivers_MCX_MCXA_MCXA366._flexio_mculcd_type.ENWRPinIndex (*C var*), 438
drivers_MCX_MCXA_MCXA366._flexio_mculcd_type.flexioBase (*C var*), 438
drivers_MCX_MCXA_MCXA366._flexio_mculcd_type.RDPinIndex (*C var*), 438
drivers_MCX_MCXA_MCXA366._flexio_mculcd_type.rxShifterEndIndex (*C var*), 438
drivers_MCX_MCXA_MCXA366._flexio_mculcd_type.rxShifterStartIndex (*C var*), 438
drivers_MCX_MCXA_MCXA366._flexio_mculcd_type.setCSPin (*C var*), 438
drivers_MCX_MCXA_MCXA366._flexio_mculcd_type.setRDWRPin (*C var*), 438
drivers_MCX_MCXA_MCXA366._flexio_mculcd_type.setRSPin (*C var*), 438
drivers_MCX_MCXA_MCXA366._flexio_mculcd_type.timerIndex (*C var*), 438
drivers_MCX_MCXA_MCXA366._flexio_mculcd_type.txShifterEndIndex (*C var*), 438
drivers_MCX_MCXA_MCXA366._flexio_mculcd_type.txShifterStartIndex (*C var*), 438
drivers_MCX_MCXA_MCXA366._flexio_pin_config (*C enum*), 381
drivers_MCX_MCXA_MCXA366._flexio_pin_config.kFLEXIO_PinConfigBidirectionOutputData (*C enumerator*), 381
drivers_MCX_MCXA_MCXA366._flexio_pin_config.kFLEXIO_PinConfigOpenDrainOrBidirection (*C enumerator*), 381
drivers_MCX_MCXA_MCXA366._flexio_pin_config.kFLEXIO_PinConfigOutput (*C enumerator*), 382

drivers_MCX_MCXA_MCXA366._flexio_pin_config.kFLEXIO_PinConfigOutputDisabled (*C enumerator*), 381
drivers_MCX_MCXA_MCXA366._flexio_pin_input_config (*C enum*), 387
drivers_MCX_MCXA_MCXA366._flexio_pin_input_config.kFLEXIO_FlagFallingEdgeEnable (*C enumerator*), 388
drivers_MCX_MCXA_MCXA366._flexio_pin_input_config.kFLEXIO_FlagRisingEdgeEnable (*C enumerator*), 388
drivers_MCX_MCXA_MCXA366._flexio_pin_input_config.kFLEXIO_InputInterruptDisabled (*C enumerator*), 387
drivers_MCX_MCXA_MCXA366._flexio_pin_input_config.kFLEXIO_InputInterruptEnable (*C enumerator*), 388
drivers_MCX_MCXA_MCXA366._flexio_pin_polarity (*C enum*), 382
drivers_MCX_MCXA_MCXA366._flexio_pin_polarity.kFLEXIO_PinActiveHigh (*C enumerator*), 382
drivers_MCX_MCXA_MCXA366._flexio_pin_polarity.kFLEXIO_PinActiveLow (*C enumerator*), 382
drivers_MCX_MCXA_MCXA366._flexio_shifter_buffer_type (*C enum*), 387
drivers_MCX_MCXA_MCXA366._flexio_shifter_buffer_type.kFLEXIO_ShifterBuffer (*C enumerator*), 387
drivers_MCX_MCXA_MCXA366._flexio_shifter_buffer_type.kFLEXIO_ShifterBufferBitByteSwapped (*C enumerator*), 387
drivers_MCX_MCXA_MCXA366._flexio_shifter_buffer_type.kFLEXIO_ShifterBufferBitSwapped (*C enumerator*), 387
drivers_MCX_MCXA_MCXA366._flexio_shifter_buffer_type.kFLEXIO_ShifterBufferByteSwapped (*C enumerator*), 387
drivers_MCX_MCXA_MCXA366._flexio_shifter_buffer_type.kFLEXIO_ShifterBufferHalfWordSwapped (*C enumerator*), 387
drivers_MCX_MCXA_MCXA366._flexio_shifter_buffer_type.kFLEXIO_ShifterBufferNibbleByteSwapped (*C enumerator*), 387
drivers_MCX_MCXA_MCXA366._flexio_shifter_buffer_type.kFLEXIO_ShifterBufferNibbleSwapped (*C enumerator*), 387
drivers_MCX_MCXA_MCXA366._flexio_shifter_config (*C struct*), 392
drivers_MCX_MCXA_MCXA366._flexio_shifter_config.inputSource (*C var*), 392
drivers_MCX_MCXA_MCXA366._flexio_shifter_config.parallelWidth (*C var*), 392
drivers_MCX_MCXA_MCXA366._flexio_shifter_config.pinConfig (*C var*), 392
drivers_MCX_MCXA_MCXA366._flexio_shifter_config.pinPolarity (*C var*), 392
drivers_MCX_MCXA_MCXA366._flexio_shifter_config.pinSelect (*C var*), 392
drivers_MCX_MCXA_MCXA366._flexio_shifter_config.shifterMode (*C var*), 392
drivers_MCX_MCXA_MCXA366._flexio_shifter_config.shifterStart (*C var*), 392
drivers_MCX_MCXA_MCXA366._flexio_shifter_config.shifterStop (*C var*), 392
drivers_MCX_MCXA_MCXA366._flexio_shifter_config.timerPolarity (*C var*), 392
drivers_MCX_MCXA_MCXA366._flexio_shifter_config.timerSelect (*C var*), 392
drivers_MCX_MCXA_MCXA366._flexio_shifter_input_source (*C enum*), 386
drivers_MCX_MCXA_MCXA366._flexio_shifter_input_source.kFLEXIO_ShifterInputFromNextShifterOutput (*C enumerator*), 386
drivers_MCX_MCXA_MCXA366._flexio_shifter_input_source.kFLEXIO_ShifterInputFromPin (*C enumerator*), 386
drivers_MCX_MCXA_MCXA366._flexio_shifter_mode (*C enum*), 385
drivers_MCX_MCXA_MCXA366._flexio_shifter_mode.kFLEXIO_ShifterDisabled (*C enumerator*), 385
drivers_MCX_MCXA_MCXA366._flexio_shifter_mode.kFLEXIO_ShifterModeLogic (*C enumerator*), 386
drivers_MCX_MCXA_MCXA366._flexio_shifter_mode.kFLEXIO_ShifterModeMatchContinuous (*C enumerator*), 386
drivers_MCX_MCXA_MCXA366._flexio_shifter_mode.kFLEXIO_ShifterModeMatchStore (*C enumerator*), 386
drivers_MCX_MCXA_MCXA366._flexio_shifter_mode.kFLEXIO_ShifterModeReceive (*C enumerator*), 385

drivers_MCX_MCXA_MCXA366._flexio_shifter_mode.kFLEXIO_ShifterModeState (*C enumerator*), 386
drivers_MCX_MCXA_MCXA366._flexio_shifter_mode.kFLEXIO_ShifterModeTransmit (*C enumerator*), 386
drivers_MCX_MCXA_MCXA366._flexio_shifter_start_bit (*C enum*), 386
drivers_MCX_MCXA_MCXA366._flexio_shifter_start_bit.kFLEXIO_ShifterStartBitDisabledLoadDataOnEnable (*C enumerator*), 386
drivers_MCX_MCXA_MCXA366._flexio_shifter_start_bit.kFLEXIO_ShifterStartBitDisabledLoadDataOnShift (*C enumerator*), 386
drivers_MCX_MCXA_MCXA366._flexio_shifter_start_bit.kFLEXIO_ShifterStartBitHigh (*C enumerator*), 387
drivers_MCX_MCXA_MCXA366._flexio_shifter_start_bit.kFLEXIO_ShifterStartBitLow (*C enumerator*), 387
drivers_MCX_MCXA_MCXA366._flexio_shifter_stop_bit (*C enum*), 386
drivers_MCX_MCXA_MCXA366._flexio_shifter_stop_bit.kFLEXIO_ShifterStopBitDisable (*C enumerator*), 386
drivers_MCX_MCXA_MCXA366._flexio_shifter_stop_bit.kFLEXIO_ShifterStopBitHigh (*C enumerator*), 386
drivers_MCX_MCXA_MCXA366._flexio_shifter_stop_bit.kFLEXIO_ShifterStopBitLow (*C enumerator*), 386
drivers_MCX_MCXA_MCXA366._flexio_shifter_timer_polarity (*C enum*), 385
drivers_MCX_MCXA_MCXA366._flexio_shifter_timer_polarity.kFLEXIO_ShifterTimerPolarityOnNegitive (*C enumerator*), 385
drivers_MCX_MCXA_MCXA366._flexio_shifter_timer_polarity.kFLEXIO_ShifterTimerPolarityOnPositive (*C enumerator*), 385
drivers_MCX_MCXA_MCXA366._flexio_spi_clock_phase (*C enum*), 451
drivers_MCX_MCXA_MCXA366._flexio_spi_clock_phase.kFLEXIO_SPI_ClockPhaseFirstEdge (*C enumerator*), 451
drivers_MCX_MCXA_MCXA366._flexio_spi_clock_phase.kFLEXIO_SPI_ClockPhaseSecondEdge (*C enumerator*), 451
drivers_MCX_MCXA_MCXA366._flexio_spi_data_bitcount_mode (*C enum*), 452
drivers_MCX_MCXA_MCXA366._flexio_spi_data_bitcount_mode.kFLEXIO_SPI_8BitMode (*C enumerator*), 452
drivers_MCX_MCXA_MCXA366._flexio_spi_data_bitcount_mode.kFLEXIO_SPI_16BitMode (*C enumerator*), 452
drivers_MCX_MCXA_MCXA366._flexio_spi_data_bitcount_mode.kFLEXIO_SPI_32BitMode (*C enumerator*), 452
drivers_MCX_MCXA_MCXA366._flexio_spi_dma_enable (*C enum*), 452
drivers_MCX_MCXA_MCXA366._flexio_spi_dma_enable.kFLEXIO_SPI_DmaAllEnable (*C enumerator*), 453
drivers_MCX_MCXA_MCXA366._flexio_spi_dma_enable.kFLEXIO_SPI_RxDmaEnable (*C enumerator*), 453
drivers_MCX_MCXA_MCXA366._flexio_spi_dma_enable.kFLEXIO_SPI_TxDmaEnable (*C enumerator*), 453
drivers_MCX_MCXA_MCXA366._flexio_spi_interrupt_enable (*C enum*), 452
drivers_MCX_MCXA_MCXA366._flexio_spi_interrupt_enable.kFLEXIO_SPI_RxFullInterruptEnable (*C enumerator*), 452
drivers_MCX_MCXA_MCXA366._flexio_spi_interrupt_enable.kFLEXIO_SPI_TxEmptyInterruptEnable (*C enumerator*), 452
drivers_MCX_MCXA_MCXA366._flexio_spi_master_config (*C struct*), 455
drivers_MCX_MCXA_MCXA366._flexio_spi_master_config.baudRate_Bps (*C var*), 455
drivers_MCX_MCXA_MCXA366._flexio_spi_master_config.dataMode (*C var*), 455
drivers_MCX_MCXA_MCXA366._flexio_spi_master_config.enableFastAccess (*C var*), 455
drivers_MCX_MCXA_MCXA366._flexio_spi_master_config.enableInDebug (*C var*), 455
drivers_MCX_MCXA_MCXA366._flexio_spi_master_config.enableInDoze (*C var*), 455
drivers_MCX_MCXA_MCXA366._flexio_spi_master_config.enableMaster (*C var*), 455
drivers_MCX_MCXA_MCXA366._flexio_spi_master_config.phase (*C var*), 455
drivers_MCX_MCXA_MCXA366._flexio_spi_master_edma_handle (*C struct*), 402

drivers_MCX_MCXA_MCXA366._flexio_spi_master_edma_handle.callback (*C var*), 403
drivers_MCX_MCXA_MCXA366._flexio_spi_master_edma_handle.nbytes (*C var*), 402
drivers_MCX_MCXA_MCXA366._flexio_spi_master_edma_handle.rxHandle (*C var*), 402
drivers_MCX_MCXA_MCXA366._flexio_spi_master_edma_handle.rxInProgress (*C var*), 402
drivers_MCX_MCXA_MCXA366._flexio_spi_master_edma_handle.transferSize (*C var*), 402
drivers_MCX_MCXA_MCXA366._flexio_spi_master_edma_handle.txHandle (*C var*), 402
drivers_MCX_MCXA_MCXA366._flexio_spi_master_edma_handle.txInProgress (*C var*), 402
drivers_MCX_MCXA_MCXA366._flexio_spi_master_edma_handle.userData (*C var*), 403
drivers_MCX_MCXA_MCXA366._flexio_spi_master_handle (*C struct*), 456
drivers_MCX_MCXA_MCXA366._flexio_spi_master_handle.bytePerFrame (*C var*), 457
drivers_MCX_MCXA_MCXA366._flexio_spi_master_handle.callback (*C var*), 457
drivers_MCX_MCXA_MCXA366._flexio_spi_master_handle.direction (*C var*), 457
drivers_MCX_MCXA_MCXA366._flexio_spi_master_handle.isCsContinuous (*C var*), 457
drivers_MCX_MCXA_MCXA366._flexio_spi_master_handle.rxData (*C var*), 456
drivers_MCX_MCXA_MCXA366._flexio_spi_master_handle.rxRemainingBytes (*C var*), 457
drivers_MCX_MCXA_MCXA366._flexio_spi_master_handle.state (*C var*), 457
drivers_MCX_MCXA_MCXA366._flexio_spi_master_handle.timer1Cfg (*C var*), 457
drivers_MCX_MCXA_MCXA366._flexio_spi_master_handle.transferSize (*C var*), 457
drivers_MCX_MCXA_MCXA366._flexio_spi_master_handle.txData (*C var*), 456
drivers_MCX_MCXA_MCXA366._flexio_spi_master_handle.txRemainingBytes (*C var*), 457
drivers_MCX_MCXA_MCXA366._flexio_spi_master_handle.userData (*C var*), 457
drivers_MCX_MCXA_MCXA366._flexio_spi_shift_direction (*C enum*), 452
drivers_MCX_MCXA_MCXA366._flexio_spi_shift_direction.kFLEXIO_SPI_LsbFirst (*C enumerator*), 452
drivers_MCX_MCXA_MCXA366._flexio_spi_shift_direction.kFLEXIO_SPI_MsbFirst (*C enumerator*), 452
drivers_MCX_MCXA_MCXA366._flexio_spi_slave_config (*C struct*), 455
drivers_MCX_MCXA_MCXA366._flexio_spi_slave_config.dataMode (*C var*), 456
drivers_MCX_MCXA_MCXA366._flexio_spi_slave_config.enableFastAccess (*C var*), 456
drivers_MCX_MCXA_MCXA366._flexio_spi_slave_config.enableInDebug (*C var*), 456
drivers_MCX_MCXA_MCXA366._flexio_spi_slave_config.enableInDoze (*C var*), 456
drivers_MCX_MCXA_MCXA366._flexio_spi_slave_config.enableSlave (*C var*), 456
drivers_MCX_MCXA_MCXA366._flexio_spi_slave_config.phase (*C var*), 456
drivers_MCX_MCXA_MCXA366._flexio_spi_status_flags (*C enum*), 452
drivers_MCX_MCXA_MCXA366._flexio_spi_status_flags.kFLEXIO_SPI_RxBufferFullFlag (*C enumerator*), 452
drivers_MCX_MCXA_MCXA366._flexio_spi_status_flags.kFLEXIO_SPI_TxBufferEmptyFlag (*C enumerator*), 452
drivers_MCX_MCXA_MCXA366._flexio_spi_transfer (*C struct*), 456
drivers_MCX_MCXA_MCXA366._flexio_spi_transfer_flags (*C enum*), 453
drivers_MCX_MCXA_MCXA366._flexio_spi_transfer_flags.kFLEXIO_SPI_8bitLsb (*C enumerator*), 453
drivers_MCX_MCXA_MCXA366._flexio_spi_transfer_flags.kFLEXIO_SPI_8bitMsb (*C enumerator*), 453
drivers_MCX_MCXA_MCXA366._flexio_spi_transfer_flags.kFLEXIO_SPI_16bitLsb (*C enumerator*), 453
drivers_MCX_MCXA_MCXA366._flexio_spi_transfer_flags.kFLEXIO_SPI_16bitMsb (*C enumerator*), 453
drivers_MCX_MCXA_MCXA366._flexio_spi_transfer_flags.kFLEXIO_SPI_32bitLsb (*C enumerator*), 453
drivers_MCX_MCXA_MCXA366._flexio_spi_transfer_flags.kFLEXIO_SPI_32bitMsb (*C enumerator*), 453
drivers_MCX_MCXA_MCXA366._flexio_spi_transfer_flags.kFLEXIO_SPI_csContinuous (*C enumerator*), 453
drivers_MCX_MCXA_MCXA366._flexio_spi_transfer.dataSize (*C var*), 456
drivers_MCX_MCXA_MCXA366._flexio_spi_transfer.flags (*C var*), 456
drivers_MCX_MCXA_MCXA366._flexio_spi_transfer.rxData (*C var*), 456
drivers_MCX_MCXA_MCXA366._flexio_spi_transfer.txData (*C var*), 456

drivers_MCX_MCXA_MCXA366._flexio_spi_type (*C struct*), 454
drivers_MCX_MCXA_MCXA366._flexio_spi_type.CSnPinIndex (*C var*), 455
drivers_MCX_MCXA_MCXA366._flexio_spi_type.flexioBase (*C var*), 454
drivers_MCX_MCXA_MCXA366._flexio_spi_type.SCKPinIndex (*C var*), 455
drivers_MCX_MCXA_MCXA366._flexio_spi_type.SDIPinIndex (*C var*), 454
drivers_MCX_MCXA_MCXA366._flexio_spi_type.SDOPinIndex (*C var*), 454
drivers_MCX_MCXA_MCXA366._flexio_spi_type.shifterIndex (*C var*), 455
drivers_MCX_MCXA_MCXA366._flexio_spi_type.timerIndex (*C var*), 455
drivers_MCX_MCXA_MCXA366._flexio_t_format_config (*C struct*), 470
drivers_MCX_MCXA_MCXA366._flexio_t_format_flags (*C enum*), 459
drivers_MCX_MCXA_MCXA366._flexio_t_format_flags.kFLEXIO_T_FORMAT_RxDataRegFullFlag (*C enumerator*), 459
drivers_MCX_MCXA_MCXA366._flexio_t_format_flags.kFLEXIO_T_FORMAT_RxOverRunFlag (*C enumerator*), 459
drivers_MCX_MCXA_MCXA366._flexio_t_format_flags.kFLEXIO_T_FORMAT_TxDataRegEmptyFlag (*C enumerator*), 459
drivers_MCX_MCXA_MCXA366._flexio_t_format_handle (*C struct*), 470
drivers_MCX_MCXA_MCXA366._flexio_t_format_interrupt_enable (*C enum*), 459
drivers_MCX_MCXA_MCXA366._flexio_t_format_interrupt_enable.kFLEXIO_T_FORMAT_RxDataRegFullInter (*C enumerator*), 459
drivers_MCX_MCXA_MCXA366._flexio_t_format_interrupt_enable.kFLEXIO_T_FORMAT_TxDataRegEmptyIn (*C enumerator*), 459
drivers_MCX_MCXA_MCXA366._flexio_t_format_transfer (*C struct*), 470
drivers_MCX_MCXA_MCXA366._flexio_t_format_transfer.___unnamed94___ (*C union*), 470
drivers_MCX_MCXA_MCXA366._flexio_t_format_transfer.___unnamed94___.data (*C var*), 471
drivers_MCX_MCXA_MCXA366._flexio_t_format_transfer.___unnamed94___.rxData (*C var*), 471
drivers_MCX_MCXA_MCXA366._flexio_t_format_transfer.___unnamed94___.txData (*C var*), 471
drivers_MCX_MCXA_MCXA366._flexio_t_format_type (*C struct*), 470
drivers_MCX_MCXA_MCXA366._flexio_t_format_user_modes (*C enum*), 459
drivers_MCX_MCXA_MCXA366._flexio_t_format_user_modes.kFLEXIO_T_FORMAT_USERMODE_ONESHO (*C enumerator*), 459
drivers_MCX_MCXA_MCXA366._flexio_t_format_user_modes.kFLEXIO_T_FORMAT_USERMODE_SYNC (*C enumerator*), 459
drivers_MCX_MCXA_MCXA366._flexio_timer_config (*C struct*), 391
drivers_MCX_MCXA_MCXA366._flexio_timer_config.pinConfig (*C var*), 391
drivers_MCX_MCXA_MCXA366._flexio_timer_config.pinPolarity (*C var*), 391
drivers_MCX_MCXA_MCXA366._flexio_timer_config.pinSelect (*C var*), 391
drivers_MCX_MCXA_MCXA366._flexio_timer_config.timerCompare (*C var*), 392
drivers_MCX_MCXA_MCXA366._flexio_timer_config.timerDecrement (*C var*), 391
drivers_MCX_MCXA_MCXA366._flexio_timer_config.timerDisable (*C var*), 391
drivers_MCX_MCXA_MCXA366._flexio_timer_config.timerEnable (*C var*), 391
drivers_MCX_MCXA_MCXA366._flexio_timer_config.timerMode (*C var*), 391
drivers_MCX_MCXA_MCXA366._flexio_timer_config.timerOutput (*C var*), 391
drivers_MCX_MCXA_MCXA366._flexio_timer_config.timerReset (*C var*), 391
drivers_MCX_MCXA_MCXA366._flexio_timer_config.timerStart (*C var*), 392
drivers_MCX_MCXA_MCXA366._flexio_timer_config.timerStop (*C var*), 391
drivers_MCX_MCXA_MCXA366._flexio_timer_config.triggerPolarity (*C var*), 391
drivers_MCX_MCXA_MCXA366._flexio_timer_config.triggerSelect (*C var*), 391
drivers_MCX_MCXA_MCXA366._flexio_timer_config.triggerSource (*C var*), 391
drivers_MCX_MCXA_MCXA366._flexio_timer_decrement_source (*C enum*), 383
drivers_MCX_MCXA_MCXA366._flexio_timer_decrement_source.kFLEXIO_TimerDecSrcOnFlexIOClockShiftTime (*C enumerator*), 383
drivers_MCX_MCXA_MCXA366._flexio_timer_decrement_source.kFLEXIO_TimerDecSrcOnPinInputShiftPinInpu (*C enumerator*), 383
drivers_MCX_MCXA_MCXA366._flexio_timer_decrement_source.kFLEXIO_TimerDecSrcOnTriggerInputShiftTime (*C enumerator*), 383
drivers_MCX_MCXA_MCXA366._flexio_timer_decrement_source.kFLEXIO_TimerDecSrcOnTriggerInputShiftTrig (*C enumerator*), 383

drivers_MCX_MCXA_MCXA366._flexio_timer_disable_condition (*C enum*), 383
drivers_MCX_MCXA_MCXA366._flexio_timer_disable_condition.kFLEXIO_TimerDisableNever (*C enumerator*), 383
drivers_MCX_MCXA_MCXA366._flexio_timer_disable_condition.kFLEXIO_TimerDisableOnPinBothEdge (*C enumerator*), 384
drivers_MCX_MCXA_MCXA366._flexio_timer_disable_condition.kFLEXIO_TimerDisableOnPinBothEdgeTriggerH (*C enumerator*), 384
drivers_MCX_MCXA_MCXA366._flexio_timer_disable_condition.kFLEXIO_TimerDisableOnPreTimerDisable (*C enumerator*), 383
drivers_MCX_MCXA_MCXA366._flexio_timer_disable_condition.kFLEXIO_TimerDisableOnTimerCompare (*C enumerator*), 384
drivers_MCX_MCXA_MCXA366._flexio_timer_disable_condition.kFLEXIO_TimerDisableOnTimerCompareTrigger (*C enumerator*), 384
drivers_MCX_MCXA_MCXA366._flexio_timer_disable_condition.kFLEXIO_TimerDisableOnTriggerFallingEdge (*C enumerator*), 384
drivers_MCX_MCXA_MCXA366._flexio_timer_enable_condition (*C enum*), 384
drivers_MCX_MCXA_MCXA366._flexio_timer_enable_condition.kFLEXIO_TimerEnabledAlways (*C enumerator*), 384
drivers_MCX_MCXA_MCXA366._flexio_timer_enable_condition.kFLEXIO_TimerEnableOnPinRisingEdge (*C enumerator*), 384
drivers_MCX_MCXA_MCXA366._flexio_timer_enable_condition.kFLEXIO_TimerEnableOnPinRisingEdgeTriggerH (*C enumerator*), 384
drivers_MCX_MCXA_MCXA366._flexio_timer_enable_condition.kFLEXIO_TimerEnableOnPrevTimerEnable (*C enumerator*), 384
drivers_MCX_MCXA_MCXA366._flexio_timer_enable_condition.kFLEXIO_TimerEnableOnTriggerBothEdge (*C enumerator*), 384
drivers_MCX_MCXA_MCXA366._flexio_timer_enable_condition.kFLEXIO_TimerEnableOnTriggerHigh (*C enumerator*), 384
drivers_MCX_MCXA_MCXA366._flexio_timer_enable_condition.kFLEXIO_TimerEnableOnTriggerHighPinHigh (*C enumerator*), 384
drivers_MCX_MCXA_MCXA366._flexio_timer_enable_condition.kFLEXIO_TimerEnableOnTriggerRisingEdge (*C enumerator*), 384
drivers_MCX_MCXA_MCXA366._flexio_timer_mode (*C enum*), 382
drivers_MCX_MCXA_MCXA366._flexio_timer_mode.kFLEXIO_TimerModeDisabled (*C enumerator*), 382
drivers_MCX_MCXA_MCXA366._flexio_timer_mode.kFLEXIO_TimerModeDual8BitBaudBit (*C enumerator*), 382
drivers_MCX_MCXA_MCXA366._flexio_timer_mode.kFLEXIO_TimerModeDual8BitPWM (*C enumerator*), 382
drivers_MCX_MCXA_MCXA366._flexio_timer_mode.kFLEXIO_TimerModeDual8BitPWMLow (*C enumerator*), 382
drivers_MCX_MCXA_MCXA366._flexio_timer_mode.kFLEXIO_TimerModeSingle16Bit (*C enumerator*), 382
drivers_MCX_MCXA_MCXA366._flexio_timer_output (*C enum*), 382
drivers_MCX_MCXA_MCXA366._flexio_timer_output_state (*C enum*), 385
drivers_MCX_MCXA_MCXA366._flexio_timer_output_state.kFLEXIO_PwmHigh (*C enumerator*), 385
drivers_MCX_MCXA_MCXA366._flexio_timer_output_state.kFLEXIO_PwmLow (*C enumerator*), 385
drivers_MCX_MCXA_MCXA366._flexio_timer_output.kFLEXIO_TimerOutputOneAffectedByReset (*C enumerator*), 382
drivers_MCX_MCXA_MCXA366._flexio_timer_output.kFLEXIO_TimerOutputOneNotAffectedByReset (*C enumerator*), 382
drivers_MCX_MCXA_MCXA366._flexio_timer_output.kFLEXIO_TimerOutputZeroAffectedByReset (*C enumerator*), 382
drivers_MCX_MCXA_MCXA366._flexio_timer_output.kFLEXIO_TimerOutputZeroNotAffectedByReset (*C enumerator*), 382
drivers_MCX_MCXA_MCXA366._flexio_timer_reset_condition (*C enum*), 383

drivers_MCX_MCXA_MCXA366._flexio_timer_reset_condition.kFLEXIO_TimerResetNever (*C enumerator*), 383
drivers_MCX_MCXA_MCXA366._flexio_timer_reset_condition.kFLEXIO_TimerResetOnTimerPinEqualToTimerO (*C enumerator*), 383
drivers_MCX_MCXA_MCXA366._flexio_timer_reset_condition.kFLEXIO_TimerResetOnTimerPinRisingEdge (*C enumerator*), 383
drivers_MCX_MCXA_MCXA366._flexio_timer_reset_condition.kFLEXIO_TimerResetOnTimerTriggerBothEdge (*C enumerator*), 383
drivers_MCX_MCXA_MCXA366._flexio_timer_reset_condition.kFLEXIO_TimerResetOnTimerTriggerEqualToTim (*C enumerator*), 383
drivers_MCX_MCXA_MCXA366._flexio_timer_reset_condition.kFLEXIO_TimerResetOnTimerTriggerRisingEdge (*C enumerator*), 383
drivers_MCX_MCXA_MCXA366._flexio_timer_start_bit_condition (*C enum*), 385
drivers_MCX_MCXA_MCXA366._flexio_timer_start_bit_condition.kFLEXIO_TimerStartBitDisabled (*C enumerator*), 385
drivers_MCX_MCXA_MCXA366._flexio_timer_start_bit_condition.kFLEXIO_TimerStartBitEnabled (*C enumerator*), 385
drivers_MCX_MCXA_MCXA366._flexio_timer_stop_bit_condition (*C enum*), 384
drivers_MCX_MCXA_MCXA366._flexio_timer_stop_bit_condition.kFLEXIO_TimerStopBitDisabled (*C enumerator*), 384
drivers_MCX_MCXA_MCXA366._flexio_timer_stop_bit_condition.kFLEXIO_TimerStopBitEnableOnTimerCompa (*C enumerator*), 385
drivers_MCX_MCXA_MCXA366._flexio_timer_stop_bit_condition.kFLEXIO_TimerStopBitEnableOnTimerCompa (*C enumerator*), 385
drivers_MCX_MCXA_MCXA366._flexio_timer_stop_bit_condition.kFLEXIO_TimerStopBitEnableOnTimerDisabl (*C enumerator*), 385
drivers_MCX_MCXA_MCXA366._flexio_timer_trigger_polarity (*C enum*), 381
drivers_MCX_MCXA_MCXA366._flexio_timer_trigger_polarity.kFLEXIO_TimerTriggerPolarityActiveHigh (*C enumerator*), 381
drivers_MCX_MCXA_MCXA366._flexio_timer_trigger_polarity.kFLEXIO_TimerTriggerPolarityActiveLow (*C enumerator*), 381
drivers_MCX_MCXA_MCXA366._flexio_timer_trigger_source (*C enum*), 381
drivers_MCX_MCXA_MCXA366._flexio_timer_trigger_source.kFLEXIO_TimerTriggerSourceExternal (*C enumerator*), 381
drivers_MCX_MCXA_MCXA366._flexio_timer_trigger_source.kFLEXIO_TimerTriggerSourceInternal (*C enumerator*), 381
drivers_MCX_MCXA_MCXA366._flexio_uart_bit_count_per_char (*C enum*), 479
drivers_MCX_MCXA_MCXA366._flexio_uart_bit_count_per_char.kFLEXIO_UART_7BitsPerChar (*C enumerator*), 479
drivers_MCX_MCXA_MCXA366._flexio_uart_bit_count_per_char.kFLEXIO_UART_8BitsPerChar (*C enumerator*), 479
drivers_MCX_MCXA_MCXA366._flexio_uart_bit_count_per_char.kFLEXIO_UART_9BitsPerChar (*C enumerator*), 479
drivers_MCX_MCXA_MCXA366._flexio_uart_config (*C struct*), 480
drivers_MCX_MCXA_MCXA366._flexio_uart_config.baudRate_Bps (*C var*), 481
drivers_MCX_MCXA_MCXA366._flexio_uart_config.bitCountPerChar (*C var*), 481
drivers_MCX_MCXA_MCXA366._flexio_uart_config.enableFastAccess (*C var*), 480
drivers_MCX_MCXA_MCXA366._flexio_uart_config.enableInDebug (*C var*), 480
drivers_MCX_MCXA_MCXA366._flexio_uart_config.enableInDoze (*C var*), 480
drivers_MCX_MCXA_MCXA366._flexio_uart_config.enableUart (*C var*), 480
drivers_MCX_MCXA_MCXA366._flexio_uart_edma_handle (*C struct*), 405
drivers_MCX_MCXA_MCXA366._flexio_uart_edma_handle.callback (*C var*), 405
drivers_MCX_MCXA_MCXA366._flexio_uart_edma_handle.nbytes (*C var*), 405
drivers_MCX_MCXA_MCXA366._flexio_uart_edma_handle.rxDataSizeAll (*C var*), 405
drivers_MCX_MCXA_MCXA366._flexio_uart_edma_handle.rxEdmaHandle (*C var*), 405
drivers_MCX_MCXA_MCXA366._flexio_uart_edma_handle.rxState (*C var*), 406
drivers_MCX_MCXA_MCXA366._flexio_uart_edma_handle.txDataSizeAll (*C var*), 405
drivers_MCX_MCXA_MCXA366._flexio_uart_edma_handle.txEdmaHandle (*C var*), 405

drivers_MCX_MCXA_MCXA366._flexio_uart_edma_handle.txState (*C var*), 406
drivers_MCX_MCXA_MCXA366._flexio_uart_edma_handle.userData (*C var*), 405
drivers_MCX_MCXA_MCXA366._flexio_uart_handle (*C struct*), 481
drivers_MCX_MCXA_MCXA366._flexio_uart_handle.callback (*C var*), 482
drivers_MCX_MCXA_MCXA366._flexio_uart_handle.rxData (*C var*), 481
drivers_MCX_MCXA_MCXA366._flexio_uart_handle.rxDataSize (*C var*), 481
drivers_MCX_MCXA_MCXA366._flexio_uart_handle.rxDataSizeAll (*C var*), 481
drivers_MCX_MCXA_MCXA366._flexio_uart_handle.rxRingBuffer (*C var*), 481
drivers_MCX_MCXA_MCXA366._flexio_uart_handle.rxRingBufferHead (*C var*), 481
drivers_MCX_MCXA_MCXA366._flexio_uart_handle.rxRingBufferSize (*C var*), 481
drivers_MCX_MCXA_MCXA366._flexio_uart_handle.rxRingBufferTail (*C var*), 482
drivers_MCX_MCXA_MCXA366._flexio_uart_handle.rxState (*C var*), 482
drivers_MCX_MCXA_MCXA366._flexio_uart_handle.txData (*C var*), 481
drivers_MCX_MCXA_MCXA366._flexio_uart_handle.txDataSize (*C var*), 481
drivers_MCX_MCXA_MCXA366._flexio_uart_handle.txDataSizeAll (*C var*), 481
drivers_MCX_MCXA_MCXA366._flexio_uart_handle.txState (*C var*), 482
drivers_MCX_MCXA_MCXA366._flexio_uart_handle.userData (*C var*), 482
drivers_MCX_MCXA_MCXA366._flexio_uart_interrupt_enable (*C enum*), 479
drivers_MCX_MCXA_MCXA366._flexio_uart_interrupt_enable.kFLEXIO_UART_RxDataRegFullInterruptEnable (*C enumerator*), 479
drivers_MCX_MCXA_MCXA366._flexio_uart_interrupt_enable.kFLEXIO_UART_TxDataRegEmptyInterruptEnab (*C enumerator*), 479
drivers_MCX_MCXA_MCXA366._flexio_uart_status_flags (*C enum*), 479
drivers_MCX_MCXA_MCXA366._flexio_uart_status_flags.kFLEXIO_UART_RxDataRegFullFlag (*C enumerator*), 479
drivers_MCX_MCXA_MCXA366._flexio_uart_status_flags.kFLEXIO_UART_RxOverRunFlag (*C enumerator*), 479
drivers_MCX_MCXA_MCXA366._flexio_uart_status_flags.kFLEXIO_UART_TxDataRegEmptyFlag (*C enumerator*), 479
drivers_MCX_MCXA_MCXA366._flexio_uart_transfer (*C struct*), 481
drivers_MCX_MCXA_MCXA366._flexio_uart_transfer.___unnamed97___ (*C union*), 482
drivers_MCX_MCXA_MCXA366._flexio_uart_transfer.___unnamed97___.data (*C var*), 482
drivers_MCX_MCXA_MCXA366._flexio_uart_transfer.___unnamed97___.rxData (*C var*), 482
drivers_MCX_MCXA_MCXA366._flexio_uart_transfer.___unnamed97___.txData (*C var*), 482
drivers_MCX_MCXA_MCXA366._flexio_uart_transfer.dataSize (*C var*), 481
drivers_MCX_MCXA_MCXA366._flexio_uart_type (*C struct*), 480
drivers_MCX_MCXA_MCXA366._flexio_uart_type.flexioBase (*C var*), 480
drivers_MCX_MCXA_MCXA366._flexio_uart_type.RxPinIndex (*C var*), 480
drivers_MCX_MCXA_MCXA366._flexio_uart_type.shifterIndex (*C var*), 480
drivers_MCX_MCXA_MCXA366._flexio_uart_type.timerIndex (*C var*), 480
drivers_MCX_MCXA_MCXA366._flexio_uart_type.TxPinIndex (*C var*), 480
drivers_MCX_MCXA_MCXA366._flexpwm_capture_channel (*C enum*), 520
drivers_MCX_MCXA_MCXA366._flexpwm_capture_channel_config (*C struct*), 539
drivers_MCX_MCXA_MCXA366._flexpwm_capture_channel_config.edge0 (*C var*), 539
drivers_MCX_MCXA_MCXA366._flexpwm_capture_channel_config.edge1 (*C var*), 539
drivers_MCX_MCXA_MCXA366._flexpwm_capture_channel_config.edgeCompareValue (*C var*), 539
drivers_MCX_MCXA_MCXA366._flexpwm_capture_channel_config.enableEdgeCounter (*C var*), 539
drivers_MCX_MCXA_MCXA366._flexpwm_capture_channel_config.fifoWatermark (*C var*), 540
drivers_MCX_MCXA_MCXA366._flexpwm_capture_channel_config.inputSelect (*C var*), 539
drivers_MCX_MCXA_MCXA366._flexpwm_capture_channel_config.oneshot (*C var*), 539
drivers_MCX_MCXA_MCXA366._flexpwm_capture_channel.kFLEXPWM_Capture_A (*C enumerator*), 520
drivers_MCX_MCXA_MCXA366._flexpwm_capture_channel.kFLEXPWM_Capture_B (*C enumerator*), 520
drivers_MCX_MCXA_MCXA366._flexpwm_capture_channel.kFLEXPWM_Capture_X (*C enumerator*), 520

drivers_MCX_MCXA_MCXA366._flexpwm_capture_edge (*C enum*), 518
drivers_MCX_MCXA_MCXA366._flexpwm_capture_edge.kFLEXPWM_CaptureEdge_Both (*C enumerator*), 518
drivers_MCX_MCXA_MCXA366._flexpwm_capture_edge.kFLEXPWM_CaptureEdge_Disabled (*C enumerator*), 518
drivers_MCX_MCXA_MCXA366._flexpwm_capture_edge.kFLEXPWM_CaptureEdge_Falling (*C enumerator*), 518
drivers_MCX_MCXA_MCXA366._flexpwm_capture_edge.kFLEXPWM_CaptureEdge_Rising (*C enumerator*), 518
drivers_MCX_MCXA_MCXA366._flexpwm_capture_fifo_watermark (*C enum*), 518
drivers_MCX_MCXA_MCXA366._flexpwm_capture_fifo_watermark.kFLEXPWM_CaptureFifoWatermark_1 (*C enumerator*), 518
drivers_MCX_MCXA_MCXA366._flexpwm_capture_fifo_watermark.kFLEXPWM_CaptureFifoWatermark_2 (*C enumerator*), 519
drivers_MCX_MCXA_MCXA366._flexpwm_capture_fifo_watermark.kFLEXPWM_CaptureFifoWatermark_3 (*C enumerator*), 519
drivers_MCX_MCXA_MCXA366._flexpwm_capture_fifo_watermark.kFLEXPWM_CaptureFifoWatermark_4 (*C enumerator*), 519
drivers_MCX_MCXA_MCXA366._flexpwm_capture_filter_channel_config (*C struct*), 540
drivers_MCX_MCXA_MCXA366._flexpwm_capture_filter_channel_config.filterCount (*C var*), 540
drivers_MCX_MCXA_MCXA366._flexpwm_capture_filter_channel_config.filterPeriod (*C var*), 540
drivers_MCX_MCXA_MCXA366._flexpwm_capture_filter_config (*C struct*), 540
drivers_MCX_MCXA_MCXA366._flexpwm_capture_filter_config.captureA (*C var*), 541
drivers_MCX_MCXA_MCXA366._flexpwm_capture_filter_config.captureB (*C var*), 541
drivers_MCX_MCXA_MCXA366._flexpwm_capture_filter_config.captureX (*C var*), 541
drivers_MCX_MCXA_MCXA366._flexpwm_capture_index (*C enum*), 519
drivers_MCX_MCXA_MCXA366._flexpwm_capture_index.kFLEXPWM_Capture_A_Edge0 (*C enumerator*), 519
drivers_MCX_MCXA_MCXA366._flexpwm_capture_index.kFLEXPWM_Capture_A_Edge1 (*C enumerator*), 519
drivers_MCX_MCXA_MCXA366._flexpwm_capture_index.kFLEXPWM_Capture_B_Edge0 (*C enumerator*), 519
drivers_MCX_MCXA_MCXA366._flexpwm_capture_index.kFLEXPWM_Capture_B_Edge1 (*C enumerator*), 520
drivers_MCX_MCXA_MCXA366._flexpwm_capture_index.kFLEXPWM_Capture_X_Edge0 (*C enumerator*), 519
drivers_MCX_MCXA_MCXA366._flexpwm_capture_index.kFLEXPWM_Capture_X_Edge1 (*C enumerator*), 519
drivers_MCX_MCXA_MCXA366._flexpwm_capture_input_select (*C enum*), 519
drivers_MCX_MCXA_MCXA366._flexpwm_capture_input_select.kFLEXPWM_CaptureInput_EdgeCounter (*C enumerator*), 519
drivers_MCX_MCXA_MCXA366._flexpwm_capture_input_select.kFLEXPWM_CaptureInput_RawSignal (*C enumerator*), 519
drivers_MCX_MCXA_MCXA366._flexpwm_clock_source (*C enum*), 512
drivers_MCX_MCXA_MCXA366._flexpwm_clock_source.kFLEXPWM_ClockSource_ExtClock (*C enumerator*), 512
drivers_MCX_MCXA_MCXA366._flexpwm_clock_source.kFLEXPWM_ClockSource_IPBusClock (*C enumerator*), 512
drivers_MCX_MCXA_MCXA366._flexpwm_clock_source.kFLEXPWM_ClockSource_Submodule0Clock (*C enumerator*), 512
drivers_MCX_MCXA_MCXA366._flexpwm_compare_mode (*C enum*), 513
drivers_MCX_MCXA_MCXA366._flexpwm_compare_mode.kFLEXPWM_CompareMode_Equal (*C enumerator*), 513
drivers_MCX_MCXA_MCXA366._flexpwm_compare_mode.kFLEXPWM_CompareMode_EqualGreater (*C enumerator*), 513
drivers_MCX_MCXA_MCXA366._flexpwm_counter_config (*C struct*), 531
drivers_MCX_MCXA_MCXA366._flexpwm_counter_config.initSource (*C var*), 531
drivers_MCX_MCXA_MCXA366._flexpwm_counter_config.initValue (*C var*), 531

drivers_MCX_MCXA_MCXA366._flexpwm_counter_config.modValue (*C var*), 531
drivers_MCX_MCXA_MCXA366._flexpwm_dma_capture_source (*C enum*), 524
drivers_MCX_MCXA_MCXA366._flexpwm_dma_capture_source.kFLEXPWM_DMADisable (*C enumerator*), 524
drivers_MCX_MCXA_MCXA366._flexpwm_dma_capture_source.kFLEXPWM_DMAFIFOWatermark (*C enumerator*), 524
drivers_MCX_MCXA_MCXA366._flexpwm_dma_capture_source.kFLEXPWM_DMALocalReload (*C enumerator*), 524
drivers_MCX_MCXA_MCXA366._flexpwm_dma_capture_source.kFLEXPWM_DMALocalSync (*C enumerator*), 524
drivers_MCX_MCXA_MCXA366._flexpwm_dma_config (*C struct*), 541
drivers_MCX_MCXA_MCXA366._flexpwm_dma_config.captureSource (*C var*), 541
drivers_MCX_MCXA_MCXA366._flexpwm_dma_config.fifoWatermarkAND (*C var*), 541
drivers_MCX_MCXA_MCXA366._flexpwm_dma_enable (*C enum*), 524
drivers_MCX_MCXA_MCXA366._flexpwm_dma_enable.kFLEXPWM_DMA_CaptureA0Enable (*C enumerator*), 525
drivers_MCX_MCXA_MCXA366._flexpwm_dma_enable.kFLEXPWM_DMA_CaptureA1Enable (*C enumerator*), 525
drivers_MCX_MCXA_MCXA366._flexpwm_dma_enable.kFLEXPWM_DMA_CaptureB0Enable (*C enumerator*), 525
drivers_MCX_MCXA_MCXA366._flexpwm_dma_enable.kFLEXPWM_DMA_CaptureB1Enable (*C enumerator*), 525
drivers_MCX_MCXA_MCXA366._flexpwm_dma_enable.kFLEXPWM_DMA_CaptureX0Enable (*C enumerator*), 525
drivers_MCX_MCXA_MCXA366._flexpwm_dma_enable.kFLEXPWM_DMA_CaptureX1Enable (*C enumerator*), 525
drivers_MCX_MCXA_MCXA366._flexpwm_dma_enable.kFLEXPWM_DMA_ValueWriteEnable (*C enumerator*), 525
drivers_MCX_MCXA_MCXA366._flexpwm_fault_clearing_mode (*C enum*), 516
drivers_MCX_MCXA_MCXA366._flexpwm_fault_clearing_mode.kFLEXPWM_FaultClearingMode_Automatic (*C enumerator*), 516
drivers_MCX_MCXA_MCXA366._flexpwm_fault_clearing_mode.kFLEXPWM_FaultClearingMode_Manual (*C enumerator*), 516
drivers_MCX_MCXA_MCXA366._flexpwm_fault_config (*C struct*), 536
drivers_MCX_MCXA_MCXA366._flexpwm_fault_config.enableCombinatorialPath (*C var*), 537
drivers_MCX_MCXA_MCXA366._flexpwm_fault_config.enableFullCycleRecovery (*C var*), 537
drivers_MCX_MCXA_MCXA366._flexpwm_fault_config.enableHalfCycleRecovery (*C var*), 537
drivers_MCX_MCXA_MCXA366._flexpwm_fault_config.enableSafetyMode (*C var*), 537
drivers_MCX_MCXA_MCXA366._flexpwm_fault_config.faultClearingMode (*C var*), 536
drivers_MCX_MCXA_MCXA366._flexpwm_fault_config.faultInputActiveLevel (*C var*), 536
drivers_MCX_MCXA_MCXA366._flexpwm_fault_filter_config (*C struct*), 537
drivers_MCX_MCXA_MCXA366._flexpwm_fault_filter_config.enableGlitchStretch (*C var*), 538
drivers_MCX_MCXA_MCXA366._flexpwm_fault_filter_config.filterCount (*C var*), 537
drivers_MCX_MCXA_MCXA366._flexpwm_fault_filter_config.filterPeriod (*C var*), 537
drivers_MCX_MCXA_MCXA366._flexpwm_fault_interrupt_enable (*C enum*), 522
drivers_MCX_MCXA_MCXA366._flexpwm_fault_interrupt_enable.kFLEXPWM_Fault0InterruptEnable (*C enumerator*), 522
drivers_MCX_MCXA_MCXA366._flexpwm_fault_interrupt_enable.kFLEXPWM_Fault1InterruptEnable (*C enumerator*), 522
drivers_MCX_MCXA_MCXA366._flexpwm_fault_interrupt_enable.kFLEXPWM_Fault2InterruptEnable (*C enumerator*), 522
drivers_MCX_MCXA_MCXA366._flexpwm_fault_interrupt_enable.kFLEXPWM_Fault3InterruptEnable (*C enumerator*), 522
drivers_MCX_MCXA_MCXA366._flexpwm_fault_mask (*C enum*), 515
drivers_MCX_MCXA_MCXA366._flexpwm_fault_mask.kFLEXPWM_FaultMask_0 (*C enumerator*), 516
drivers_MCX_MCXA_MCXA366._flexpwm_fault_mask.kFLEXPWM_FaultMask_1 (*C enumerator*), 516

drivers_MCX_MCXA_MCXA366._flexpwm_fault_mask.kFLEXPWM_FaultMask_2 (*C enumerator*), 516
drivers_MCX_MCXA_MCXA366._flexpwm_fault_mask.kFLEXPWM_FaultMask_3 (*C enumerator*), 516
drivers_MCX_MCXA_MCXA366._flexpwm_fault_output_behavior (*C enum*), 515
drivers_MCX_MCXA_MCXA366._flexpwm_fault_output_behavior.kFLEXPWM_FaultOutput_Force0 (*C enumerator*), 515
drivers_MCX_MCXA_MCXA366._flexpwm_fault_output_behavior.kFLEXPWM_FaultOutput_Force1 (*C enumerator*), 515
drivers_MCX_MCXA_MCXA366._flexpwm_fault_output_behavior.kFLEXPWM_FaultOutput_HighZ (*C enumerator*), 515
drivers_MCX_MCXA_MCXA366._flexpwm_fault_output_config (*C struct*), 535
drivers_MCX_MCXA_MCXA366._flexpwm_fault_output_config.disableMask_ch0 (*C var*), 536
drivers_MCX_MCXA_MCXA366._flexpwm_fault_output_config.outputBehavior (*C var*), 536
drivers_MCX_MCXA_MCXA366._flexpwm_fault_pin_status (*C enum*), 523
drivers_MCX_MCXA_MCXA366._flexpwm_fault_pin_status.kFLEXPWM_Fault0PinActive (*C enumerator*), 524
drivers_MCX_MCXA_MCXA366._flexpwm_fault_pin_status.kFLEXPWM_Fault1PinActive (*C enumerator*), 524
drivers_MCX_MCXA_MCXA366._flexpwm_fault_pin_status.kFLEXPWM_Fault2PinActive (*C enumerator*), 524
drivers_MCX_MCXA_MCXA366._flexpwm_fault_pin_status.kFLEXPWM_Fault3PinActive (*C enumerator*), 524
drivers_MCX_MCXA_MCXA366._flexpwm_fault_status_flag (*C enum*), 523
drivers_MCX_MCXA_MCXA366._flexpwm_fault_status_flag.kFLEXPWM_Fault0Flag (*C enumerator*), 523
drivers_MCX_MCXA_MCXA366._flexpwm_fault_status_flag.kFLEXPWM_Fault1Flag (*C enumerator*), 523
drivers_MCX_MCXA_MCXA366._flexpwm_fault_status_flag.kFLEXPWM_Fault2Flag (*C enumerator*), 523
drivers_MCX_MCXA_MCXA366._flexpwm_fault_status_flag.kFLEXPWM_Fault3Flag (*C enumerator*), 523
drivers_MCX_MCXA_MCXA366._flexpwm_fault_submodule_config (*C struct*), 536
drivers_MCX_MCXA_MCXA366._flexpwm_fault_submodule_config.pwma (*C var*), 536
drivers_MCX_MCXA_MCXA366._flexpwm_fault_submodule_config.pwmb (*C var*), 536
drivers_MCX_MCXA_MCXA366._flexpwm_fault_submodule_config.pwmx (*C var*), 536
drivers_MCX_MCXA_MCXA366._flexpwm_force_out_channel_config (*C struct*), 534
drivers_MCX_MCXA_MCXA366._flexpwm_force_out_channel_config.softwareValue (*C var*), 535
drivers_MCX_MCXA_MCXA366._flexpwm_force_out_channel_config.source (*C var*), 535
drivers_MCX_MCXA_MCXA366._flexpwm_force_out_config (*C struct*), 535
drivers_MCX_MCXA_MCXA366._flexpwm_force_out_config.forceSource (*C var*), 535
drivers_MCX_MCXA_MCXA366._flexpwm_force_out_config.pwma (*C var*), 535
drivers_MCX_MCXA_MCXA366._flexpwm_force_out_config.pwma_initialValue (*C var*), 535
drivers_MCX_MCXA_MCXA366._flexpwm_force_out_config.pwmb (*C var*), 535
drivers_MCX_MCXA_MCXA366._flexpwm_force_out_config.pwmb_initialValue (*C var*), 535
drivers_MCX_MCXA_MCXA366._flexpwm_force_out_config.pwmx_initialValue (*C var*), 535
drivers_MCX_MCXA_MCXA366._flexpwm_force_output_source (*C enum*), 514
drivers_MCX_MCXA_MCXA366._flexpwm_force_output_source.kFLEXPWM_ForceOutputSource_ExtForce (*C enumerator*), 515
drivers_MCX_MCXA_MCXA366._flexpwm_force_output_source.kFLEXPWM_ForceOutputSource_ExtSync (*C enumerator*), 515
drivers_MCX_MCXA_MCXA366._flexpwm_force_output_source.kFLEXPWM_ForceOutputSource_LocalForce (*C enumerator*), 514
drivers_MCX_MCXA_MCXA366._flexpwm_force_output_source.kFLEXPWM_ForceOutputSource_LocalReload (*C enumerator*), 514
drivers_MCX_MCXA_MCXA366._flexpwm_force_output_source.kFLEXPWM_ForceOutputSource_LocalSync (*C enumerator*), 515
drivers_MCX_MCXA_MCXA366._flexpwm_force_output_source.kFLEXPWM_ForceOutputSource_MasterForce

(*C enumerator*), 514
drivers_MCX_MCXA_MCXA366._flexpwm_force_output_source.kFLEXPWM_ForceOutputSource_MasterReload (*C enumerator*), 515
drivers_MCX_MCXA_MCXA366._flexpwm_force_output_source.kFLEXPWM_ForceOutputSource_MasterSync (*C enumerator*), 515
drivers_MCX_MCXA_MCXA366._flexpwm_force_pwm_source (*C enum*), 515
drivers_MCX_MCXA_MCXA366._flexpwm_force_pwm_source.kFLEXPWM_ForcePwmSource_External (*C enumerator*), 515
drivers_MCX_MCXA_MCXA366._flexpwm_force_pwm_source.kFLEXPWM_ForcePwmSource_Generated (*C enumerator*), 515
drivers_MCX_MCXA_MCXA366._flexpwm_force_pwm_source.kFLEXPWM_ForcePwmSource_Inverted (*C enumerator*), 515
drivers_MCX_MCXA_MCXA366._flexpwm_force_pwm_source.kFLEXPWM_ForcePwmSource_Software (*C enumerator*), 515
drivers_MCX_MCXA_MCXA366._flexpwm_init_source (*C enum*), 513
drivers_MCX_MCXA_MCXA366._flexpwm_init_source.kFLEXPWM_InitSource_ExtSync (*C enumerator*), 513
drivers_MCX_MCXA_MCXA366._flexpwm_init_source.kFLEXPWM_InitSource_LocalSync (*C enumerator*), 513
drivers_MCX_MCXA_MCXA366._flexpwm_init_source.kFLEXPWM_InitSource_MasterReload (*C enumerator*), 513
drivers_MCX_MCXA_MCXA366._flexpwm_init_source.kFLEXPWM_InitSource_MasterSync (*C enumerator*), 513
drivers_MCX_MCXA_MCXA366._flexpwm_input_capture_config (*C struct*), 540
drivers_MCX_MCXA_MCXA366._flexpwm_input_capture_config.captureA (*C var*), 540
drivers_MCX_MCXA_MCXA366._flexpwm_input_capture_config.captureB (*C var*), 540
drivers_MCX_MCXA_MCXA366._flexpwm_input_capture_config.captureX (*C var*), 540
drivers_MCX_MCXA_MCXA366._flexpwm_ipol_source (*C enum*), 514
drivers_MCX_MCXA_MCXA366._flexpwm_ipol_source.kFLEXPWM_IPOL_PWM23 (*C enumerator*), 514
drivers_MCX_MCXA_MCXA366._flexpwm_ipol_source.kFLEXPWM_IPOL_PWM45 (*C enumerator*), 514
drivers_MCX_MCXA_MCXA366._flexpwm_load_mode (*C enum*), 513
drivers_MCX_MCXA_MCXA366._flexpwm_load_mode.kFLEXPWM_LoadMode_Immediate (*C enumerator*), 513
drivers_MCX_MCXA_MCXA366._flexpwm_load_mode.kFLEXPWM_LoadMode_Opportunity (*C enumerator*), 513
drivers_MCX_MCXA_MCXA366._flexpwm_output_trigger_config (*C struct*), 538
drivers_MCX_MCXA_MCXA366._flexpwm_output_trigger_config.muxTrig0Source (*C var*), 538
drivers_MCX_MCXA_MCXA366._flexpwm_output_trigger_config.muxTrig1Source (*C var*), 538
drivers_MCX_MCXA_MCXA366._flexpwm_output_trigger_config.outTriggerEnable (*C var*), 538
drivers_MCX_MCXA_MCXA366._flexpwm_output_trigger_config.stretchPrescaler (*C var*), 539
drivers_MCX_MCXA_MCXA366._flexpwm_output_trigger_config.triggerFrequency (*C var*), 539
drivers_MCX_MCXA_MCXA366._flexpwm_output_trigger_mask (*C enum*), 517
drivers_MCX_MCXA_MCXA366._flexpwm_output_trigger_mask.kFLEXPWM_OutputTriggerMask_VAL0 (*C enumerator*), 518
drivers_MCX_MCXA_MCXA366._flexpwm_output_trigger_mask.kFLEXPWM_OutputTriggerMask_VAL1 (*C enumerator*), 518
drivers_MCX_MCXA_MCXA366._flexpwm_output_trigger_mask.kFLEXPWM_OutputTriggerMask_VAL2 (*C enumerator*), 518
drivers_MCX_MCXA_MCXA366._flexpwm_output_trigger_mask.kFLEXPWM_OutputTriggerMask_VAL3 (*C enumerator*), 518
drivers_MCX_MCXA_MCXA366._flexpwm_output_trigger_mask.kFLEXPWM_OutputTriggerMask_VAL4 (*C enumerator*), 518
drivers_MCX_MCXA_MCXA366._flexpwm_output_trigger_mask.kFLEXPWM_OutputTriggerMask_VAL5 (*C enumerator*), 518
drivers_MCX_MCXA_MCXA366._flexpwm_prescaler (*C enum*), 512
drivers_MCX_MCXA_MCXA366._flexpwm_prescaler.kFLEXPWM_Prescale_Divide_1 (*C enumer-*

ator), 512
drivers_MCX_MCXA_MCXA366._flexpwm_prescaler.kFLEXPWM_Prescale_Divide_2 (*C enumerator*), 512
drivers_MCX_MCXA_MCXA366._flexpwm_prescaler.kFLEXPWM_Prescale_Divide_4 (*C enumerator*), 512
drivers_MCX_MCXA_MCXA366._flexpwm_prescaler.kFLEXPWM_Prescale_Divide_8 (*C enumerator*), 512
drivers_MCX_MCXA_MCXA366._flexpwm_prescaler.kFLEXPWM_Prescale_Divide_16 (*C enumerator*), 512
drivers_MCX_MCXA_MCXA366._flexpwm_prescaler.kFLEXPWM_Prescale_Divide_32 (*C enumerator*), 512
drivers_MCX_MCXA_MCXA366._flexpwm_prescaler.kFLEXPWM_Prescale_Divide_64 (*C enumerator*), 512
drivers_MCX_MCXA_MCXA366._flexpwm_prescaler.kFLEXPWM_Prescale_Divide_128 (*C enumerator*), 513
drivers_MCX_MCXA_MCXA366._flexpwm_pwm_channel_config (*C struct*), 533
drivers_MCX_MCXA_MCXA366._flexpwm_pwm_channel_config.compareValue_OFF (*C var*), 533
drivers_MCX_MCXA_MCXA366._flexpwm_pwm_channel_config.compareValue_ON (*C var*), 533
drivers_MCX_MCXA_MCXA366._flexpwm_pwm_channel_config.polarity (*C var*), 534
drivers_MCX_MCXA_MCXA366._flexpwm_pwm_config (*C struct*), 534
drivers_MCX_MCXA_MCXA366._flexpwm_pwm_config.complementary (*C var*), 534
drivers_MCX_MCXA_MCXA366._flexpwm_pwm_config.ipolSource (*C var*), 534
drivers_MCX_MCXA_MCXA366._flexpwm_pwm_config.pwma (*C var*), 534
drivers_MCX_MCXA_MCXA366._flexpwm_pwm_config.pwmb (*C var*), 534
drivers_MCX_MCXA_MCXA366._flexpwm_pwm_polarity (*C enum*), 514
drivers_MCX_MCXA_MCXA366._flexpwm_pwm_polarity.kFLEXPWM_Polarity_ActiveHigh (*C enumerator*), 514
drivers_MCX_MCXA_MCXA366._flexpwm_pwm_polarity.kFLEXPWM_Polarity_ActiveLow (*C enumerator*), 514
drivers_MCX_MCXA_MCXA366._flexpwm_reload_config (*C struct*), 532
drivers_MCX_MCXA_MCXA366._flexpwm_reload_config.enableFullCycleReload (*C var*), 532
drivers_MCX_MCXA_MCXA366._flexpwm_reload_config.enableHalfCycleReload (*C var*), 532
drivers_MCX_MCXA_MCXA366._flexpwm_reload_config.halfCycleValue (*C var*), 532
drivers_MCX_MCXA_MCXA366._flexpwm_reload_config.loadFrequency (*C var*), 532
drivers_MCX_MCXA_MCXA366._flexpwm_reload_config.loadMode (*C var*), 532
drivers_MCX_MCXA_MCXA366._flexpwm_reload_config.reloadSource (*C var*), 532
drivers_MCX_MCXA_MCXA366._flexpwm_reload_source (*C enum*), 513
drivers_MCX_MCXA_MCXA366._flexpwm_reload_source.kFLEXPWM_ReloadSource_LocalReload (*C enumerator*), 513
drivers_MCX_MCXA_MCXA366._flexpwm_reload_source.kFLEXPWM_ReloadSource_MasterReload (*C enumerator*), 513
drivers_MCX_MCXA_MCXA366._flexpwm_stretch_prescaler (*C enum*), 517
drivers_MCX_MCXA_MCXA366._flexpwm_stretch_prescaler.kFLEXPWM_StretchPrescaler_2Clocks (*C enumerator*), 517
drivers_MCX_MCXA_MCXA366._flexpwm_stretch_prescaler.kFLEXPWM_StretchPrescaler_4Clocks (*C enumerator*), 517
drivers_MCX_MCXA_MCXA366._flexpwm_stretch_prescaler.kFLEXPWM_StretchPrescaler_8Clocks (*C enumerator*), 517
drivers_MCX_MCXA_MCXA366._flexpwm_stretch_prescaler.kFLEXPWM_StretchPrescaler_None (*C enumerator*), 517
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_config (*C struct*), 532
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_config.clockSource (*C var*), 533
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_config.counterConfig (*C var*), 533
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_config.enableDebugMode (*C var*), 533
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_config.prescaler (*C var*), 533
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_config.reloadConfig (*C var*), 533
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_interrupt_enable (*C enum*), 520
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_interrupt_enable.kFLEXPWM_CaptureA0InterruptEnable

(*C enumerator*), 521
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_interrupt_enable.kFLEXPWM_CaptureA1InterruptEnable
(*C enumerator*), 521
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_interrupt_enable.kFLEXPWM_CaptureB0InterruptEnable
(*C enumerator*), 521
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_interrupt_enable.kFLEXPWM_CaptureB1InterruptEnable
(*C enumerator*), 521
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_interrupt_enable.kFLEXPWM_CaptureX0InterruptEnable
(*C enumerator*), 520
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_interrupt_enable.kFLEXPWM_CaptureX1InterruptEnable
(*C enumerator*), 520
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_interrupt_enable.kFLEXPWM_Compare0InterruptEnable
(*C enumerator*), 520
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_interrupt_enable.kFLEXPWM_Compare1InterruptEnable
(*C enumerator*), 520
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_interrupt_enable.kFLEXPWM_Compare2InterruptEnable
(*C enumerator*), 520
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_interrupt_enable.kFLEXPWM_Compare3InterruptEnable
(*C enumerator*), 520
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_interrupt_enable.kFLEXPWM_Compare4InterruptEnable
(*C enumerator*), 520
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_interrupt_enable.kFLEXPWM_Compare5InterruptEnable
(*C enumerator*), 520
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_interrupt_enable.kFLEXPWM_ReloadErrorInterruptEnabl
(*C enumerator*), 521
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_interrupt_enable.kFLEXPWM_ReloadInterruptEnable
(*C enumerator*), 521
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_mask (*C enum*), 514
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_mask.kFLEXPWM_SubmoduleMask_0 (*C enumerator*), 514
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_mask.kFLEXPWM_SubmoduleMask_1 (*C enumerator*), 514
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_mask.kFLEXPWM_SubmoduleMask_2 (*C enumerator*), 514
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_status_flag (*C enum*), 521
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_status_flag.kFLEXPWM_CaptureA0Flag
(*C enumerator*), 522
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_status_flag.kFLEXPWM_CaptureA1Flag
(*C enumerator*), 522
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_status_flag.kFLEXPWM_CaptureB0Flag
(*C enumerator*), 522
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_status_flag.kFLEXPWM_CaptureB1Flag
(*C enumerator*), 522
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_status_flag.kFLEXPWM_CaptureX0Flag
(*C enumerator*), 521
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_status_flag.kFLEXPWM_CaptureX1Flag
(*C enumerator*), 522
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_status_flag.kFLEXPWM_Compare0Flag
(*C enumerator*), 521
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_status_flag.kFLEXPWM_Compare1Flag
(*C enumerator*), 521
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_status_flag.kFLEXPWM_Compare2Flag
(*C enumerator*), 521
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_status_flag.kFLEXPWM_Compare3Flag
(*C enumerator*), 521
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_status_flag.kFLEXPWM_Compare4Flag
(*C enumerator*), 521
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_status_flag.kFLEXPWM_Compare5Flag

(*C enumerator*), 521
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_status_flag.kFLEXPWM_RegisterUpdatedFlag (*C enumerator*), 522
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_status_flag.kFLEXPWM_ReloadErrorFlag (*C enumerator*), 522
drivers_MCX_MCXA_MCXA366._flexpwm_submodule_status_flag.kFLEXPWM_ReloadFlag (*C enumerator*), 522
drivers_MCX_MCXA_MCXA366._flexpwm_trigger_frequency (*C enum*), 517
drivers_MCX_MCXA_MCXA366._flexpwm_trigger_frequency.kFLEXPWM_TriggerFrequency_EveryCycle (*C enumerator*), 517
drivers_MCX_MCXA_MCXA366._flexpwm_trigger_frequency.kFLEXPWM_TriggerFrequency_OnReload (*C enumerator*), 517
drivers_MCX_MCXA_MCXA366._flexpwm_trigger_mux_source (*C enum*), 517
drivers_MCX_MCXA_MCXA366._flexpwm_trigger_mux_source.kFLEXPWM_TriggerMuxSource_GeneratedTrigge (*C enumerator*), 517
drivers_MCX_MCXA_MCXA366._flexpwm_trigger_mux_source.kFLEXPWM_TriggerMuxSource_PWMOutput (*C enumerator*), 517
drivers_MCX_MCXA_MCXA366._flexpwm_write_protect (*C enum*), 516
drivers_MCX_MCXA_MCXA366._flexpwm_write_protect.kFLEXPWM_WriteProtect_Off (*C enumerator*), 516
drivers_MCX_MCXA_MCXA366._flexpwm_write_protect.kFLEXPWM_WriteProtect_OffLocked (*C enumerator*), 516
drivers_MCX_MCXA_MCXA366._flexpwm_write_protect.kFLEXPWM_WriteProtect_On (*C enumerator*), 516
drivers_MCX_MCXA_MCXA366._flexpwm_write_protect.kFLEXPWM_WriteProtect_OnLocked (*C enumerator*), 517
drivers_MCX_MCXA_MCXA366._freq_measure_config (*C struct*), 658
drivers_MCX_MCXA_MCXA366._freq_measure_config.enableContinuousMode (*C var*), 658
drivers_MCX_MCXA_MCXA366._freq_measure_config.operateMode (*C var*), 658
drivers_MCX_MCXA_MCXA366._freq_measure_config.operateModeAttribute (*C var*), 658
drivers_MCX_MCXA_MCXA366._freqme_interrupt_enable (*C enum*), 656
drivers_MCX_MCXA_MCXA366._freqme_interrupt_enable.kFREQME_OverflowInterruptEnable (*C enumerator*), 656
drivers_MCX_MCXA_MCXA366._freqme_interrupt_enable.kFREQME_ReadyInterruptEnable (*C enumerator*), 657
drivers_MCX_MCXA_MCXA366._freqme_interrupt_enable.kFREQME_UnderflowInterruptEnable (*C enumerator*), 656
drivers_MCX_MCXA_MCXA366._freqme_interrupt_status_flags (*C enum*), 656
drivers_MCX_MCXA_MCXA366._freqme_interrupt_status_flags.kFREQME_AllInterruptStatusFlags (*C enumerator*), 656
drivers_MCX_MCXA_MCXA366._freqme_interrupt_status_flags.kFREQME_OverflowInterruptStatusFlag (*C enumerator*), 656
drivers_MCX_MCXA_MCXA366._freqme_interrupt_status_flags.kFREQME_ReadyInterruptStatusFlag (*C enumerator*), 656
drivers_MCX_MCXA_MCXA366._freqme_interrupt_status_flags.kFREQME_UnderflowInterruptStatusFlag (*C enumerator*), 656
drivers_MCX_MCXA_MCXA366._freqme_mode_attribute (*C union*), 657
drivers_MCX_MCXA_MCXA366._freqme_mode_attribute.pulsePolarity (*C var*), 658
drivers_MCX_MCXA_MCXA366._freqme_mode_attribute.refClkScaleFactor (*C var*), 658
drivers_MCX_MCXA_MCXA366._freqme_operate_mode (*C enum*), 657
drivers_MCX_MCXA_MCXA366._freqme_operate_mode.kFREOME_PulseWidthMeasurementMode (*C enumerator*), 657
drivers_MCX_MCXA_MCXA366._freqme_operate_mode.kFREQME_FreqMeasurementMode (*C enumerator*), 657
drivers_MCX_MCXA_MCXA366._freqme_pulse_polarity (*C enum*), 657
drivers_MCX_MCXA_MCXA366._freqme_pulse_polarity.kFREQME_PulseHighPeriod (*C enumerator*), 657
drivers_MCX_MCXA_MCXA366._freqme_pulse_polarity.kFREQME_PulseLowPeriod (*C enumera-*

tor), 657
drivers_MCX_MCXA_MCXA366._gpio_checker_attribute (*C enum*), 546
drivers_MCX_MCXA_MCXA366._gpio_checker_attribute.kGPIO_IgnoreAttributeCheck (*C enumerator*), 547
drivers_MCX_MCXA_MCXA366._gpio_checker_attribute.kGPIO_UsernonsecureNUsersecureNPrivilegedsecureN (*C enumerator*), 547
drivers_MCX_MCXA_MCXA366._gpio_checker_attribute.kGPIO_UsernonsecureNUsersecureNPrivilegedsecureR (*C enumerator*), 547
drivers_MCX_MCXA_MCXA366._gpio_checker_attribute.kGPIO_UsernonsecureNUsersecureNPrivilegedsecureRW (*C enumerator*), 547
drivers_MCX_MCXA_MCXA366._gpio_checker_attribute.kGPIO_UsernonsecureNUsersecureRPrivilegedsecureRW (*C enumerator*), 547
drivers_MCX_MCXA_MCXA366._gpio_checker_attribute.kGPIO_UsernonsecureNUsersecureRWPrivilegedsecureRW (*C enumerator*), 547
drivers_MCX_MCXA_MCXA366._gpio_checker_attribute.kGPIO_UsernonsecureRUsersecureRPrivilegedsecureRW (*C enumerator*), 547
drivers_MCX_MCXA_MCXA366._gpio_checker_attribute.kGPIO_UsernonsecureRUsersecureRWPrivilegedsecureRW (*C enumerator*), 547
drivers_MCX_MCXA_MCXA366._gpio_checker_attribute.kGPIO_UsernonsecureRWUsersecureRWPrivilegedsecureI (*C enumerator*), 546
drivers_MCX_MCXA_MCXA366._gpio_interrupt_config (*C enum*), 547
drivers_MCX_MCXA_MCXA366._gpio_interrupt_config.kGPIO_ActiveHighTriggerOutputEnable (*C enumerator*), 548
drivers_MCX_MCXA_MCXA366._gpio_interrupt_config.kGPIO_ActiveLowTriggerOutputEnable (*C enumerator*), 548
drivers_MCX_MCXA_MCXA366._gpio_interrupt_config.kGPIO_DMAEitherEdge (*C enumerator*), 547
drivers_MCX_MCXA_MCXA366._gpio_interrupt_config.kGPIO_DMAFallingEdge (*C enumerator*), 547
drivers_MCX_MCXA_MCXA366._gpio_interrupt_config.kGPIO_DMARisingEdge (*C enumerator*), 547
drivers_MCX_MCXA_MCXA366._gpio_interrupt_config.kGPIO_FlagEitherEdge (*C enumerator*), 547
drivers_MCX_MCXA_MCXA366._gpio_interrupt_config.kGPIO_FlagFallingEdge (*C enumerator*), 547
drivers_MCX_MCXA_MCXA366._gpio_interrupt_config.kGPIO_FlagRisingEdge (*C enumerator*), 547
drivers_MCX_MCXA_MCXA366._gpio_interrupt_config.kGPIO_InterruptEitherEdge (*C enumerator*), 548
drivers_MCX_MCXA_MCXA366._gpio_interrupt_config.kGPIO_InterruptFallingEdge (*C enumerator*), 548
drivers_MCX_MCXA_MCXA366._gpio_interrupt_config.kGPIO_InterruptLogicOne (*C enumerator*), 548
drivers_MCX_MCXA_MCXA366._gpio_interrupt_config.kGPIO_InterruptLogicZero (*C enumerator*), 548
drivers_MCX_MCXA_MCXA366._gpio_interrupt_config.kGPIO_InterruptRisingEdge (*C enumerator*), 548
drivers_MCX_MCXA_MCXA366._gpio_interrupt_config.kGPIO_InterruptStatusFlagDisabled (*C enumerator*), 547
drivers_MCX_MCXA_MCXA366._gpio_interrupt_selection (*C enum*), 548
drivers_MCX_MCXA_MCXA366._gpio_interrupt_selection.kGPIO_InterruptOutput0 (*C enumerator*), 548
drivers_MCX_MCXA_MCXA366._gpio_interrupt_selection.kGPIO_InterruptOutput1 (*C enumerator*), 548
drivers_MCX_MCXA_MCXA366._gpio_pin_config (*C struct*), 549
drivers_MCX_MCXA_MCXA366._gpio_pin_config.outputLogic (*C var*), 549
drivers_MCX_MCXA_MCXA366._gpio_pin_config.pinDirection (*C var*), 549
drivers_MCX_MCXA_MCXA366._gpio_pin_direction (*C enum*), 546

drivers_MCX_MCXA_MCXA366._gpio_pin_direction.kGPIO_DigitalInput (*C enumerator*), 546
drivers_MCX_MCXA_MCXA366._gpio_pin_direction.kGPIO_DigitalOutput (*C enumerator*), 546
drivers_MCX_MCXA_MCXA366._gpio_version_info (*C struct*), 549
drivers_MCX_MCXA_MCXA366._gpio_version_info.feature (*C var*), 549
drivers_MCX_MCXA_MCXA366._gpio_version_info.major (*C var*), 550
drivers_MCX_MCXA_MCXA366._gpio_version_info.minor (*C var*), 549
drivers_MCX_MCXA_MCXA366._i3c_baudrate (*C struct*), 588
drivers_MCX_MCXA_MCXA366._i3c_baudrate.i2cBaud (*C var*), 588
drivers_MCX_MCXA_MCXA366._i3c_baudrate.i3cOpenDrainBaud (*C var*), 588
drivers_MCX_MCXA_MCXA366._i3c_baudrate.i3cPushPullBaud (*C var*), 588
drivers_MCX_MCXA_MCXA366._i3c_bus_request (*C enum*), 581
drivers_MCX_MCXA_MCXA366._i3c_bus_request.kI3C_RequestAutoIbi (*C enumerator*), 582
drivers_MCX_MCXA_MCXA366._i3c_bus_request.kI3C_RequestEmitStartAddr (*C enumerator*), 582
drivers_MCX_MCXA_MCXA366._i3c_bus_request.kI3C_RequestEmitStop (*C enumerator*), 582
drivers_MCX_MCXA_MCXA366._i3c_bus_request.kI3C_RequestForceExit (*C enumerator*), 582
drivers_MCX_MCXA_MCXA366._i3c_bus_request.kI3C_RequestIbiAckNack (*C enumerator*), 582
drivers_MCX_MCXA_MCXA366._i3c_bus_request.kI3C_RequestNone (*C enumerator*), 582
drivers_MCX_MCXA_MCXA366._i3c_bus_request.kI3C_RequestProcessDAA (*C enumerator*), 582
drivers_MCX_MCXA_MCXA366._i3c_bus_type (*C enum*), 582
drivers_MCX_MCXA_MCXA366._i3c_bus_type.kI3C_TypeI2C (*C enumerator*), 582
drivers_MCX_MCXA_MCXA366._i3c_bus_type.kI3C_TypeI3CDdr (*C enumerator*), 582
drivers_MCX_MCXA_MCXA366._i3c_bus_type.kI3C_TypeI3CSdr (*C enumerator*), 582
drivers_MCX_MCXA_MCXA366._i3c_config (*C struct*), 559
drivers_MCX_MCXA_MCXA366._i3c_config.baudRate_Hz (*C var*), 560
drivers_MCX_MCXA_MCXA366._i3c_config.bcr (*C var*), 560
drivers_MCX_MCXA_MCXA366._i3c_config.dcr (*C var*), 560
drivers_MCX_MCXA_MCXA366._i3c_config.disableTimeout (*C var*), 560
drivers_MCX_MCXA_MCXA366._i3c_config.enableMaster (*C var*), 560
drivers_MCX_MCXA_MCXA366._i3c_config.enableOpenDrainHigh (*C var*), 560
drivers_MCX_MCXA_MCXA366._i3c_config.enableOpenDrainStop (*C var*), 560
drivers_MCX_MCXA_MCXA366._i3c_config.enableSlave (*C var*), 560
drivers_MCX_MCXA_MCXA366._i3c_config.hdrMode (*C var*), 561
drivers_MCX_MCXA_MCXA366._i3c_config.hKeep (*C var*), 560
drivers_MCX_MCXA_MCXA366._i3c_config.ignoreS0S1Error (*C var*), 561
drivers_MCX_MCXA_MCXA366._i3c_config.masterDynamicAddress (*C var*), 560
drivers_MCX_MCXA_MCXA366._i3c_config.matchSlaveStartStop (*C var*), 561
drivers_MCX_MCXA_MCXA366._i3c_config.maxReadLength (*C var*), 560
drivers_MCX_MCXA_MCXA366._i3c_config.maxWriteLength (*C var*), 560
drivers_MCX_MCXA_MCXA366._i3c_config.nakAllRequest (*C var*), 561
drivers_MCX_MCXA_MCXA366._i3c_config.offline (*C var*), 561
drivers_MCX_MCXA_MCXA366._i3c_config.partNumber (*C var*), 560
drivers_MCX_MCXA_MCXA366._i3c_config.restartSclDelay (*C var*), 560
drivers_MCX_MCXA_MCXA366._i3c_config.startSclDelay (*C var*), 560
drivers_MCX_MCXA_MCXA366._i3c_config.staticAddr (*C var*), 560
drivers_MCX_MCXA_MCXA366._i3c_config.vendorID (*C var*), 560
drivers_MCX_MCXA_MCXA366._i3c_device_info (*C struct*), 557
drivers_MCX_MCXA_MCXA366._i3c_device_info.bcr (*C var*), 558
drivers_MCX_MCXA_MCXA366._i3c_device_info.dcr (*C var*), 558
drivers_MCX_MCXA_MCXA366._i3c_device_info.dynamicAddr (*C var*), 558
drivers_MCX_MCXA_MCXA366._i3c_device_info.hdrMode (*C var*), 558
drivers_MCX_MCXA_MCXA366._i3c_device_info.maxReadLength (*C var*), 558
drivers_MCX_MCXA_MCXA366._i3c_device_info.maxWriteLength (*C var*), 558
drivers_MCX_MCXA_MCXA366._i3c_device_info.partNumber (*C var*), 558
drivers_MCX_MCXA_MCXA366._i3c_device_info.staticAddr (*C var*), 558
drivers_MCX_MCXA_MCXA366._i3c_device_info.vendorID (*C var*), 558
drivers_MCX_MCXA_MCXA366._i3c_direction (*C enum*), 583
drivers_MCX_MCXA_MCXA366._i3c_direction.kI3C_Read (*C enumerator*), 583

drivers_MCX_MCXA_MCXA366._i3c_direction.kI3C_Write (*C enumerator*), 583
drivers_MCX_MCXA_MCXA366._i3c_hdr_mode (*C enum*), 557
drivers_MCX_MCXA_MCXA366._i3c_hdr_mode.kI3C_HDRModeDDR (*C enumerator*), 557
drivers_MCX_MCXA_MCXA366._i3c_hdr_mode.kI3C_HDRModeNone (*C enumerator*), 557
drivers_MCX_MCXA_MCXA366._i3c_hdr_mode.kI3C_HDRModeTSL (*C enumerator*), 557
drivers_MCX_MCXA_MCXA366._i3c_hdr_mode.kI3C_HDRModeTSP (*C enumerator*), 557
drivers_MCX_MCXA_MCXA366._i3c_ibi_response (*C enum*), 582
drivers_MCX_MCXA_MCXA366._i3c_ibi_response.kI3C_IbiRespAck (*C enumerator*), 582
drivers_MCX_MCXA_MCXA366._i3c_ibi_response.kI3C_IbiRespAckMandatory (*C enumerator*), 582
drivers_MCX_MCXA_MCXA366._i3c_ibi_response.kI3C_IbiRespManual (*C enumerator*), 583
drivers_MCX_MCXA_MCXA366._i3c_ibi_response.kI3C_IbiRespNack (*C enumerator*), 582
drivers_MCX_MCXA_MCXA366._i3c_ibi_state (*C enum*), 583
drivers_MCX_MCXA_MCXA366._i3c_ibi_state.kI3C_IbiAckNackPending (*C enumerator*), 583
drivers_MCX_MCXA_MCXA366._i3c_ibi_state.kI3C_IbiDataBuffNeed (*C enumerator*), 583
drivers_MCX_MCXA_MCXA366._i3c_ibi_state.kI3C_IbiReady (*C enumerator*), 583
drivers_MCX_MCXA_MCXA366._i3c_ibi_type (*C enum*), 583
drivers_MCX_MCXA_MCXA366._i3c_ibi_type.kI3C_IbiHotJoin (*C enumerator*), 583
drivers_MCX_MCXA_MCXA366._i3c_ibi_type.kI3C_IbiMasterRequest (*C enumerator*), 583
drivers_MCX_MCXA_MCXA366._i3c_ibi_type.kI3C_IbiNormal (*C enumerator*), 583
drivers_MCX_MCXA_MCXA366._i3c_legacy_i2c_speed_mode (*C enum*), 585
drivers_MCX_MCXA_MCXA366._i3c_legacy_i2c_speed_mode.kI3C_LegacyI2CFastMode (*C enumerator*), 585
drivers_MCX_MCXA_MCXA366._i3c_legacy_i2c_speed_mode.kI3C_LegacyI2CFastModePlus (*C enumerator*), 585
drivers_MCX_MCXA_MCXA366._i3c_legacy_i2c_speed_mode.kI3C_LegacyI2CStandardMode (*C enumerator*), 585
drivers_MCX_MCXA_MCXA366._i3c_master_baudrate_config (*C struct*), 589
drivers_MCX_MCXA_MCXA366._i3c_master_baudrate_config.busMode (*C var*), 589
drivers_MCX_MCXA_MCXA366._i3c_master_baudrate_config.enableODHPP (*C var*), 589
drivers_MCX_MCXA_MCXA366._i3c_master_baudrate_config.i2cBaud (*C var*), 589
drivers_MCX_MCXA_MCXA366._i3c_master_baudrate_config.i3cOpenDrainBaud (*C var*), 589
drivers_MCX_MCXA_MCXA366._i3c_master_baudrate_config.i3cPushPullBaud (*C var*), 589
drivers_MCX_MCXA_MCXA366._i3c_master_bus_mode (*C enum*), 585
drivers_MCX_MCXA_MCXA366._i3c_master_bus_mode.kI3C_LimitedBus (*C enumerator*), 585
drivers_MCX_MCXA_MCXA366._i3c_master_bus_mode.kI3C_MixedFastBus (*C enumerator*), 585
drivers_MCX_MCXA_MCXA366._i3c_master_bus_mode.kI3C_PureBus (*C enumerator*), 585
drivers_MCX_MCXA_MCXA366._i3c_master_config (*C struct*), 590
drivers_MCX_MCXA_MCXA366._i3c_master_config.baudRate_Hz (*C var*), 590
drivers_MCX_MCXA_MCXA366._i3c_master_config.disableTimeout (*C var*), 590
drivers_MCX_MCXA_MCXA366._i3c_master_config.enableMaster (*C var*), 590
drivers_MCX_MCXA_MCXA366._i3c_master_config.enableOpenDrainHigh (*C var*), 590
drivers_MCX_MCXA_MCXA366._i3c_master_config.enableOpenDrainStop (*C var*), 590
drivers_MCX_MCXA_MCXA366._i3c_master_config.hKeep (*C var*), 590
drivers_MCX_MCXA_MCXA366._i3c_master_config.restartSclDelay (*C var*), 590
drivers_MCX_MCXA_MCXA366._i3c_master_config.startSclDelay (*C var*), 590
drivers_MCX_MCXA_MCXA366._i3c_master_daa_baudrate (*C struct*), 588
drivers_MCX_MCXA_MCXA366._i3c_master_daa_baudrate.i3cOpenDrainBaud (*C var*), 589
drivers_MCX_MCXA_MCXA366._i3c_master_daa_baudrate.i3cPushPullBaud (*C var*), 589
drivers_MCX_MCXA_MCXA366._i3c_master_daa_baudrate.sourceClock_Hz (*C var*), 588
drivers_MCX_MCXA_MCXA366._i3c_master_edma_callback (*C struct*), 594
drivers_MCX_MCXA_MCXA366._i3c_master_edma_callback.ibiCallback (*C var*), 594
drivers_MCX_MCXA_MCXA366._i3c_master_edma_callback.slave2Master (*C var*), 594
drivers_MCX_MCXA_MCXA366._i3c_master_edma_callback.transferComplete (*C var*), 594
drivers_MCX_MCXA_MCXA366._i3c_master_edma_handle (*C struct*), 594
drivers_MCX_MCXA_MCXA366._i3c_master_edma_handle.base (*C var*), 595
drivers_MCX_MCXA_MCXA366._i3c_master_edma_handle.callback (*C var*), 595

drivers_MCX_MCXA_MCXA366._i3c_master_edma_handle.ibiAddress (*C var*), 595
drivers_MCX_MCXA_MCXA366._i3c_master_edma_handle.ibiBuff (*C var*), 595
drivers_MCX_MCXA_MCXA366._i3c_master_edma_handle.ibiFlag (*C var*), 595
drivers_MCX_MCXA_MCXA366._i3c_master_edma_handle.ibiPayloadSize (*C var*), 595
drivers_MCX_MCXA_MCXA366._i3c_master_edma_handle.ibiType (*C var*), 596
drivers_MCX_MCXA_MCXA366._i3c_master_edma_handle.result (*C var*), 596
drivers_MCX_MCXA_MCXA366._i3c_master_edma_handle.rxDmaHandle (*C var*), 595
drivers_MCX_MCXA_MCXA366._i3c_master_edma_handle.state (*C var*), 595
drivers_MCX_MCXA_MCXA366._i3c_master_edma_handle.subaddressBuffer (*C var*), 595
drivers_MCX_MCXA_MCXA366._i3c_master_edma_handle.subaddressCount (*C var*), 595
drivers_MCX_MCXA_MCXA366._i3c_master_edma_handle.transfer (*C var*), 595
drivers_MCX_MCXA_MCXA366._i3c_master_edma_handle.transferCount (*C var*), 595
drivers_MCX_MCXA_MCXA366._i3c_master_edma_handle.txDmaHandle (*C var*), 595
drivers_MCX_MCXA_MCXA366._i3c_master_edma_handle.userData (*C var*), 595
drivers_MCX_MCXA_MCXA366._i3c_master_enable (*C enum*), 581
drivers_MCX_MCXA_MCXA366._i3c_master_enable.kI3C_MasterCapable (*C enumerator*), 581
drivers_MCX_MCXA_MCXA366._i3c_master_enable.kI3C_MasterOff (*C enumerator*), 581
drivers_MCX_MCXA_MCXA366._i3c_master_enable.kI3C_MasterOn (*C enumerator*), 581
drivers_MCX_MCXA_MCXA366._i3c_master_error_flags (*C enum*), 579
drivers_MCX_MCXA_MCXA366._i3c_master_error_flags.kI3C_MasterAllErrorFlags (*C enumerator*), 580
drivers_MCX_MCXA_MCXA366._i3c_master_error_flags.kI3C_MasterErrorCrcFlag (*C enumerator*), 580
drivers_MCX_MCXA_MCXA366._i3c_master_error_flags.kI3C_MasterErrorInvalidReqFlag (*C enumerator*), 580
drivers_MCX_MCXA_MCXA366._i3c_master_error_flags.kI3C_MasterErrorMsgFlag (*C enumerator*), 580
drivers_MCX_MCXA_MCXA366._i3c_master_error_flags.kI3C_MasterErrorNackFlag (*C enumerator*), 580
drivers_MCX_MCXA_MCXA366._i3c_master_error_flags.kI3C_MasterErrorParityFlag (*C enumerator*), 580
drivers_MCX_MCXA_MCXA366._i3c_master_error_flags.kI3C_MasterErrorReadFlag (*C enumerator*), 580
drivers_MCX_MCXA_MCXA366._i3c_master_error_flags.kI3C_MasterErrorTimeoutFlag (*C enumerator*), 580
drivers_MCX_MCXA_MCXA366._i3c_master_error_flags.kI3C_MasterErrorWriteAbortFlag (*C enumerator*), 580
drivers_MCX_MCXA_MCXA366._i3c_master_error_flags.kI3C_MasterErrorWriteFlag (*C enumerator*), 580
drivers_MCX_MCXA_MCXA366._i3c_master_flags (*C enum*), 578
drivers_MCX_MCXA_MCXA366._i3c_master_flags.kI3C_MasterArbitrationWonFlag (*C enumerator*), 579
drivers_MCX_MCXA_MCXA366._i3c_master_flags.kI3C_MasterBetweenFlag (*C enumerator*), 579
drivers_MCX_MCXA_MCXA366._i3c_master_flags.kI3C_MasterClearFlags (*C enumerator*), 579
drivers_MCX_MCXA_MCXA366._i3c_master_flags.kI3C_MasterCompleteFlag (*C enumerator*), 579
drivers_MCX_MCXA_MCXA366._i3c_master_flags.kI3C_MasterControlDoneFlag (*C enumerator*), 579
drivers_MCX_MCXA_MCXA366._i3c_master_flags.kI3C_MasterErrorFlag (*C enumerator*), 579
drivers_MCX_MCXA_MCXA366._i3c_master_flags.kI3C_MasterNackDetectFlag (*C enumerator*), 579
drivers_MCX_MCXA_MCXA366._i3c_master_flags.kI3C_MasterRxReadyFlag (*C enumerator*), 579
drivers_MCX_MCXA_MCXA366._i3c_master_flags.kI3C_MasterSlave2MasterFlag (*C enumerator*), 579
drivers_MCX_MCXA_MCXA366._i3c_master_flags.kI3C_MasterSlaveStartFlag (*C enumerator*), 579
drivers_MCX_MCXA_MCXA366._i3c_master_flags.kI3C_MasterTxReadyFlag (*C enumerator*),

579
drivers_MCX_MCXA_MCXA366._i3c_master_handle (*C struct*), 592
drivers_MCX_MCXA_MCXA366._i3c_master_handle.callback (*C var*), 592
drivers_MCX_MCXA_MCXA366._i3c_master_handle.ibiAddress (*C var*), 592
drivers_MCX_MCXA_MCXA366._i3c_master_handle.ibiBuff (*C var*), 592
drivers_MCX_MCXA_MCXA366._i3c_master_handle.ibiPayloadSize (*C var*), 592
drivers_MCX_MCXA_MCXA366._i3c_master_handle.ibiType (*C var*), 592
drivers_MCX_MCXA_MCXA366._i3c_master_handle.remainingBytes (*C var*), 592
drivers_MCX_MCXA_MCXA366._i3c_master_handle.rxTermOps (*C var*), 592
drivers_MCX_MCXA_MCXA366._i3c_master_handle.state (*C var*), 592
drivers_MCX_MCXA_MCXA366._i3c_master_handle.transfer (*C var*), 592
drivers_MCX_MCXA_MCXA366._i3c_master_handle.userData (*C var*), 592
drivers_MCX_MCXA_MCXA366._i3c_master_hkeep (*C enum*), 581
drivers_MCX_MCXA_MCXA366._i3c_master_hkeep.kI3C_MasterHighKeeperNone (*C enumerator*), 581
drivers_MCX_MCXA_MCXA366._i3c_master_hkeep.kI3C_MasterHighKeeperWiredIn (*C enumerator*), 581
drivers_MCX_MCXA_MCXA366._i3c_master_hkeep.kI3C_MasterPassiveSDA (*C enumerator*), 581
drivers_MCX_MCXA_MCXA366._i3c_master_hkeep.kI3C_MasterPassiveSDASCL (*C enumerator*), 581
drivers_MCX_MCXA_MCXA366._i3c_master_src_clk (*C enum*), 585
drivers_MCX_MCXA_MCXA366._i3c_master_src_clk.kI3C_MasterSrcClk24M (*C enumerator*), 585
drivers_MCX_MCXA_MCXA366._i3c_master_src_clk.kI3C_MasterSrcClk25M (*C enumerator*), 585
drivers_MCX_MCXA_MCXA366._i3c_master_state (*C enum*), 580
drivers_MCX_MCXA_MCXA366._i3c_master_state.kI3C_MasterStateDaa (*C enumerator*), 581
drivers_MCX_MCXA_MCXA366._i3c_master_state.kI3C_MasterStateDdr (*C enumerator*), 581
drivers_MCX_MCXA_MCXA366._i3c_master_state.kI3C_MasterStateIbiAck (*C enumerator*), 581
drivers_MCX_MCXA_MCXA366._i3c_master_state.kI3C_MasterStateIbiRcv (*C enumerator*), 581
drivers_MCX_MCXA_MCXA366._i3c_master_state.kI3C_MasterStateIdle (*C enumerator*), 580
drivers_MCX_MCXA_MCXA366._i3c_master_state.kI3C_MasterStateMsgSdr (*C enumerator*), 580
drivers_MCX_MCXA_MCXA366._i3c_master_state.kI3C_MasterStateNormAct (*C enumerator*), 581
drivers_MCX_MCXA_MCXA366._i3c_master_state.kI3C_MasterStateSlvReq (*C enumerator*), 580
drivers_MCX_MCXA_MCXA366._i3c_master_transfer (*C struct*), 591
drivers_MCX_MCXA_MCXA366._i3c_master_transfer_callback (*C struct*), 590
drivers_MCX_MCXA_MCXA366._i3c_master_transfer_callback.ibiCallback (*C var*), 591
drivers_MCX_MCXA_MCXA366._i3c_master_transfer_callback.slave2Master (*C var*), 591
drivers_MCX_MCXA_MCXA366._i3c_master_transfer_callback.transferComplete (*C var*), 591
drivers_MCX_MCXA_MCXA366._i3c_master_transfer_flags (*C enum*), 585
drivers_MCX_MCXA_MCXA366._i3c_master_transfer_flags.kI3C_TransferDefaultFlag (*C enumerator*), 585
drivers_MCX_MCXA_MCXA366._i3c_master_transfer_flags.kI3C_TransferDisableRxTermFlag (*C enumerator*), 586
drivers_MCX_MCXA_MCXA366._i3c_master_transfer_flags.kI3C_TransferNoStartFlag (*C enumerator*), 586
drivers_MCX_MCXA_MCXA366._i3c_master_transfer_flags.kI3C_TransferNoStopFlag (*C enumerator*), 586
drivers_MCX_MCXA_MCXA366._i3c_master_transfer_flags.kI3C_TransferRepeatedStartFlag (*C enumerator*), 586
drivers_MCX_MCXA_MCXA366._i3c_master_transfer_flags.kI3C_TransferRxAutoTermFlag (*C enumerator*), 586
drivers_MCX_MCXA_MCXA366._i3c_master_transfer_flags.kI3C_TransferStartWithBroadcastAddr (*C enumerator*), 586
drivers_MCX_MCXA_MCXA366._i3c_master_transfer_flags.kI3C_TransferWordsFlag (*C enumerator*), 586
drivers_MCX_MCXA_MCXA366._i3c_master_transfer.busType (*C var*), 591

drivers_MCX_MCXA_MCXA366._i3c_master_transfer.data (*C var*), 591
drivers_MCX_MCXA_MCXA366._i3c_master_transfer.dataSize (*C var*), 591
drivers_MCX_MCXA_MCXA366._i3c_master_transfer.direction (*C var*), 591
drivers_MCX_MCXA_MCXA366._i3c_master_transfer.flags (*C var*), 591
drivers_MCX_MCXA_MCXA366._i3c_master_transfer.ibiResponse (*C var*), 591
drivers_MCX_MCXA_MCXA366._i3c_master_transfer.slaveAddress (*C var*), 591
drivers_MCX_MCXA_MCXA366._i3c_master_transfer.subaddress (*C var*), 591
drivers_MCX_MCXA_MCXA366._i3c_master_transfer.subaddressSize (*C var*), 591
drivers_MCX_MCXA_MCXA366._i3c_register_ibi_addr (*C struct*), 588
drivers_MCX_MCXA_MCXA366._i3c_register_ibi_addr.address (*C var*), 588
drivers_MCX_MCXA_MCXA366._i3c_register_ibi_addr.i3cFastStart (*C var*), 588
drivers_MCX_MCXA_MCXA366._i3c_register_ibi_addr.ibiHasPayload (*C var*), 588
drivers_MCX_MCXA_MCXA366._i3c_rx_term_ops (*C enum*), 584
drivers_MCX_MCXA_MCXA366._i3c_rx_term_ops.kI3C_RxAutoTerm (*C enumerator*), 584
drivers_MCX_MCXA_MCXA366._i3c_rx_term_ops.kI3C_RxTermDisable (*C enumerator*), 584
drivers_MCX_MCXA_MCXA366._i3c_rx_term_ops.kI3C_RxTermLastByte (*C enumerator*), 584
drivers_MCX_MCXA_MCXA366._i3c_rx_trigger_level (*C enum*), 584
drivers_MCX_MCXA_MCXA366._i3c_rx_trigger_level.kI3C_RxTriggerOnNotEmpty (*C enumerator*), 584
drivers_MCX_MCXA_MCXA366._i3c_rx_trigger_level.kI3C_RxTriggerUntilOneHalfOrMore (*C enumerator*), 584
drivers_MCX_MCXA_MCXA366._i3c_rx_trigger_level.kI3C_RxTriggerUntilOneQuarterOrMore (*C enumerator*), 584
drivers_MCX_MCXA_MCXA366._i3c_rx_trigger_level.kI3C_RxTriggerUntilThreeQuarterOrMore (*C enumerator*), 584
drivers_MCX_MCXA_MCXA366._i3c_slave_activity_state (*C enum*), 605
drivers_MCX_MCXA_MCXA366._i3c_slave_activity_state.kI3C_SlaveLatency1Ms (*C enumerator*), 605
drivers_MCX_MCXA_MCXA366._i3c_slave_activity_state.kI3C_SlaveLatency10S (*C enumerator*), 606
drivers_MCX_MCXA_MCXA366._i3c_slave_activity_state.kI3C_SlaveLatency100Ms (*C enumerator*), 606
drivers_MCX_MCXA_MCXA366._i3c_slave_activity_state.kI3C_SlaveNoLatency (*C enumerator*), 605
drivers_MCX_MCXA_MCXA366._i3c_slave_config (*C struct*), 607
drivers_MCX_MCXA_MCXA366._i3c_slave_config.bcr (*C var*), 608
drivers_MCX_MCXA_MCXA366._i3c_slave_config.dcr (*C var*), 608
drivers_MCX_MCXA_MCXA366._i3c_slave_config.enableSlave (*C var*), 608
drivers_MCX_MCXA_MCXA366._i3c_slave_config.hdrMode (*C var*), 608
drivers_MCX_MCXA_MCXA366._i3c_slave_config.ignoreS0S1Error (*C var*), 608
drivers_MCX_MCXA_MCXA366._i3c_slave_config.matchSlaveStartStop (*C var*), 608
drivers_MCX_MCXA_MCXA366._i3c_slave_config.maxReadLength (*C var*), 608
drivers_MCX_MCXA_MCXA366._i3c_slave_config.maxWriteLength (*C var*), 608
drivers_MCX_MCXA_MCXA366._i3c_slave_config.nakAllRequest (*C var*), 608
drivers_MCX_MCXA_MCXA366._i3c_slave_config.offline (*C var*), 608
drivers_MCX_MCXA_MCXA366._i3c_slave_config.partNumber (*C var*), 608
drivers_MCX_MCXA_MCXA366._i3c_slave_config.staticAddr (*C var*), 608
drivers_MCX_MCXA_MCXA366._i3c_slave_config.vendorID (*C var*), 608
drivers_MCX_MCXA_MCXA366._i3c_slave_edma_handle (*C struct*), 612
drivers_MCX_MCXA_MCXA366._i3c_slave_edma_handle.base (*C var*), 612
drivers_MCX_MCXA_MCXA366._i3c_slave_edma_handle.callback (*C var*), 612
drivers_MCX_MCXA_MCXA366._i3c_slave_edma_handle.eventMask (*C var*), 612
drivers_MCX_MCXA_MCXA366._i3c_slave_edma_handle.isBusy (*C var*), 612
drivers_MCX_MCXA_MCXA366._i3c_slave_edma_handle.isDdrMode (*C var*), 612
drivers_MCX_MCXA_MCXA366._i3c_slave_edma_handle.rxDmaHandle (*C var*), 613
drivers_MCX_MCXA_MCXA366._i3c_slave_edma_handle.transfer (*C var*), 612
drivers_MCX_MCXA_MCXA366._i3c_slave_edma_handle.txDmaHandle (*C var*), 613
drivers_MCX_MCXA_MCXA366._i3c_slave_edma_handle.userData (*C var*), 613

drivers_MCX_MCXA_MCXA366._i3c_slave_edma_handle.wasTransmit (*C var*), 612
drivers_MCX_MCXA_MCXA366._i3c_slave_edma_transfer (*C struct*), 611
drivers_MCX_MCXA_MCXA366._i3c_slave_edma_transfer.completionStatus (*C var*), 612
drivers_MCX_MCXA_MCXA366._i3c_slave_edma_transfer.event (*C var*), 612
drivers_MCX_MCXA_MCXA366._i3c_slave_edma_transfer.rxData (*C var*), 612
drivers_MCX_MCXA_MCXA366._i3c_slave_edma_transfer.rxDataSize (*C var*), 612
drivers_MCX_MCXA_MCXA366._i3c_slave_edma_transfer.txData (*C var*), 612
drivers_MCX_MCXA_MCXA366._i3c_slave_edma_transfer.txDataSize (*C var*), 612
drivers_MCX_MCXA_MCXA366._i3c_slave_error_flags (*C enum*), 604
drivers_MCX_MCXA_MCXA366._i3c_slave_error_flags.kI3C_SlaveErrorHdrCRCFlag (*C enumerator*), 605
drivers_MCX_MCXA_MCXA366._i3c_slave_error_flags.kI3C_SlaveErrorHdrParityFlag (*C enumerator*), 605
drivers_MCX_MCXA_MCXA366._i3c_slave_error_flags.kI3C_SlaveErrorInvalidStartFlag (*C enumerator*), 605
drivers_MCX_MCXA_MCXA366._i3c_slave_error_flags.kI3C_SlaveErrorOverreadFlag (*C enumerator*), 605
drivers_MCX_MCXA_MCXA366._i3c_slave_error_flags.kI3C_SlaveErrorOverrunFlag (*C enumerator*), 604
drivers_MCX_MCXA_MCXA366._i3c_slave_error_flags.kI3C_SlaveErrorOverwriteFlag (*C enumerator*), 605
drivers_MCX_MCXA_MCXA366._i3c_slave_error_flags.kI3C_SlaveErrorS0S1Flag (*C enumerator*), 605
drivers_MCX_MCXA_MCXA366._i3c_slave_error_flags.kI3C_SlaveErrorSdrParityFlag (*C enumerator*), 605
drivers_MCX_MCXA_MCXA366._i3c_slave_error_flags.kI3C_SlaveErrorTermFlag (*C enumerator*), 604
drivers_MCX_MCXA_MCXA366._i3c_slave_error_flags.kI3C_SlaveErrorUnderrunFlag (*C enumerator*), 604
drivers_MCX_MCXA_MCXA366._i3c_slave_error_flags.kI3C_SlaveErrorUnderrunNakFlag (*C enumerator*), 604
drivers_MCX_MCXA_MCXA366._i3c_slave_event (*C enum*), 605
drivers_MCX_MCXA_MCXA366._i3c_slave_event.kI3C_SlaveEventHotJoinReq (*C enumerator*), 605
drivers_MCX_MCXA_MCXA366._i3c_slave_event.kI3C_SlaveEventIBI (*C enumerator*), 605
drivers_MCX_MCXA_MCXA366._i3c_slave_event.kI3C_SlaveEventMasterReq (*C enumerator*), 605
drivers_MCX_MCXA_MCXA366._i3c_slave_event.kI3C_SlaveEventNormal (*C enumerator*), 605
drivers_MCX_MCXA_MCXA366._i3c_slave_flags (*C enum*), 602
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveAllIrqFlags (*C enumerator*), 604
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveBusDAAFlag (*C enumerator*), 603
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveBusHDRModeFlag (*C enumerator*), 603
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveBusStartFlag (*C enumerator*), 603
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveBusStopFlag (*C enumerator*), 603
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveCCCHandledFlag (*C enumerator*), 604
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveClearFlags (*C enumerator*), 604
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveDynamicAddrChangedFlag (*C enumerator*), 603
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveErrorFlag (*C enumerator*), 604
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveEventSentFlag (*C enumerator*), 604
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveHDRCommandMatchFlag (*C enumerator*), 604
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveHotJoinDisabledFlag (*C enumerator*), 604
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveIbiDisableFlag (*C enumerator*), 604
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveMasterRequestDisabledFlag (*C enu-*

merator), 604
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveMatchedFlag (*C enumerator*), 603
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveMessageFlag (*C enumerator*), 603
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveNotStopFlag (*C enumerator*), 603
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveReceivedCCCFlag (*C enumerator*), 604
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveRequiredReadFlag (*C enumerator*), 603
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveRequiredWriteFlag (*C enumerator*), 603
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveRxReadyFlag (*C enumerator*), 603
drivers_MCX_MCXA_MCXA366._i3c_slave_flags.kI3C_SlaveTxReadyFlag (*C enumerator*), 603
drivers_MCX_MCXA_MCXA366._i3c_slave_handle (*C struct*), 609
drivers_MCX_MCXA_MCXA366._i3c_slave_handle.callback (*C var*), 610
drivers_MCX_MCXA_MCXA366._i3c_slave_handle.eventMask (*C var*), 609
drivers_MCX_MCXA_MCXA366._i3c_slave_handle.isBusy (*C var*), 609
drivers_MCX_MCXA_MCXA366._i3c_slave_handle.transfer (*C var*), 609
drivers_MCX_MCXA_MCXA366._i3c_slave_handle.transferredCount (*C var*), 609
drivers_MCX_MCXA_MCXA366._i3c_slave_handle.txFifoSize (*C var*), 610
drivers_MCX_MCXA_MCXA366._i3c_slave_handle.userData (*C var*), 610
drivers_MCX_MCXA_MCXA366._i3c_slave_handle.wasTransmit (*C var*), 609
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer (*C struct*), 608
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer_event (*C enum*), 606
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer_event.kI3C_SlaveAddressMatchEvent (*C enumerator*), 606
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer_event.kI3C_SlaveAllEvents (*C enumerator*), 606
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer_event.kI3C_SlaveCompletionEvent (*C enumerator*), 606
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer_event.kI3C_SlaveHDRCommandMatchEvent (*C enumerator*), 606
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer_event.kI3C_SlaveReceivedCCCEvent (*C enumerator*), 606
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer_event.kI3C_SlaveReceiveEvent (*C enumerator*), 606
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer_event.kI3C_SlaveRequestSentEvent (*C enumerator*), 606
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer_event.kI3C_SlaveRequiredTransmitEvent (*C enumerator*), 606
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer_event.kI3C_SlaveStartEvent (*C enumerator*), 606
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer_event.kI3C_SlaveTransmitEvent (*C enumerator*), 606
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer.completionStatus (*C var*), 609
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer.event (*C var*), 609
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer.rxData (*C var*), 609
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer.rxDataSize (*C var*), 609
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer.transferredCount (*C var*), 609
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer.txData (*C var*), 609
drivers_MCX_MCXA_MCXA366._i3c_slave_transfer.txDataSize (*C var*), 609
drivers_MCX_MCXA_MCXA366._i3c_start_scl_delay (*C enum*), 584
drivers_MCX_MCXA_MCXA366._i3c_start_scl_delay.kI3C_IncreaseSclHalfPeriod (*C enumerator*), 584
drivers_MCX_MCXA_MCXA366._i3c_start_scl_delay.kI3C_IncreaseSclOneAndHalfPeriod (*C enumerator*), 585
drivers_MCX_MCXA_MCXA366._i3c_start_scl_delay.kI3C_IncreaseSclOnePeriod (*C enumerator*), 584
drivers_MCX_MCXA_MCXA366._i3c_start_scl_delay.kI3C_NoDelay (*C enumerator*), 584

drivers_MCX_MCXA_MCXA366._i3c_timing (*C struct*), 589
drivers_MCX_MCXA_MCXA366._i3c_timing.actualI2cBaud (*C var*), 590
drivers_MCX_MCXA_MCXA366._i3c_timing.actualOdBaud (*C var*), 590
drivers_MCX_MCXA_MCXA366._i3c_timing.actualPpBaud (*C var*), 590
drivers_MCX_MCXA_MCXA366._i3c_timing.i2cBaud (*C var*), 590
drivers_MCX_MCXA_MCXA366._i3c_timing.odBaud (*C var*), 589
drivers_MCX_MCXA_MCXA366._i3c_timing.odHighPP (*C var*), 589
drivers_MCX_MCXA_MCXA366._i3c_timing.ppBaud (*C var*), 589
drivers_MCX_MCXA_MCXA366._i3c_timing.ppLow (*C var*), 589
drivers_MCX_MCXA_MCXA366._i3c_tx_trigger_level (*C enum*), 583
drivers_MCX_MCXA_MCXA366._i3c_tx_trigger_level.kI3C_TxTriggerOnEmpty (*C enumerator*), 583
drivers_MCX_MCXA_MCXA366._i3c_tx_trigger_level.kI3C_TxTriggerUntilOneHalfOrLess (*C enumerator*), 584
drivers_MCX_MCXA_MCXA366._i3c_tx_trigger_level.kI3C_TxTriggerUntilOneLessThanFull (*C enumerator*), 584
drivers_MCX_MCXA_MCXA366._i3c_tx_trigger_level.kI3C_TxTriggerUntilOneQuarterOrLess (*C enumerator*), 583
drivers_MCX_MCXA_MCXA366._lpadc_calibration_value (*C struct*), 652
drivers_MCX_MCXA_MCXA366._lpadc_conversion_average_mode (*C enum*), 635
drivers_MCX_MCXA_MCXA366._lpadc_conversion_average_mode.kLPADC_ConversionAverage1 (*C enumerator*), 635
drivers_MCX_MCXA_MCXA366._lpadc_conversion_average_mode.kLPADC_ConversionAverage2 (*C enumerator*), 635
drivers_MCX_MCXA_MCXA366._lpadc_conversion_average_mode.kLPADC_ConversionAverage4 (*C enumerator*), 635
drivers_MCX_MCXA_MCXA366._lpadc_conversion_average_mode.kLPADC_ConversionAverage8 (*C enumerator*), 635
drivers_MCX_MCXA_MCXA366._lpadc_conversion_average_mode.kLPADC_ConversionAverage16 (*C enumerator*), 635
drivers_MCX_MCXA_MCXA366._lpadc_conversion_average_mode.kLPADC_ConversionAverage32 (*C enumerator*), 636
drivers_MCX_MCXA_MCXA366._lpadc_conversion_average_mode.kLPADC_ConversionAverage64 (*C enumerator*), 636
drivers_MCX_MCXA_MCXA366._lpadc_conversion_average_mode.kLPADC_ConversionAverage128 (*C enumerator*), 636
drivers_MCX_MCXA_MCXA366._lpadc_conversion_average_mode.kLPADC_ConversionAverageMax (*C enumerator*), 636
drivers_MCX_MCXA_MCXA366._lpadc_conversion_resolution_mode (*C enum*), 635
drivers_MCX_MCXA_MCXA366._lpadc_conversion_resolution_mode.kLPADC_ConversionResolutionHigh (*C enumerator*), 635
drivers_MCX_MCXA_MCXA366._lpadc_conversion_resolution_mode.kLPADC_ConversionResolutionStandard (*C enumerator*), 635
drivers_MCX_MCXA_MCXA366._lpadc_hardware_average_mode (*C enum*), 633
drivers_MCX_MCXA_MCXA366._lpadc_hardware_average_mode.kLPADC_HardwareAverageCount1 (*C enumerator*), 633
drivers_MCX_MCXA_MCXA366._lpadc_hardware_average_mode.kLPADC_HardwareAverageCount2 (*C enumerator*), 633
drivers_MCX_MCXA_MCXA366._lpadc_hardware_average_mode.kLPADC_HardwareAverageCount4 (*C enumerator*), 633
drivers_MCX_MCXA_MCXA366._lpadc_hardware_average_mode.kLPADC_HardwareAverageCount8 (*C enumerator*), 633
drivers_MCX_MCXA_MCXA366._lpadc_hardware_average_mode.kLPADC_HardwareAverageCount16 (*C enumerator*), 633
drivers_MCX_MCXA_MCXA366._lpadc_hardware_average_mode.kLPADC_HardwareAverageCount32 (*C enumerator*), 634
drivers_MCX_MCXA_MCXA366._lpadc_hardware_average_mode.kLPADC_HardwareAverageCount64 (*C enumerator*), 634

drivers_MCX_MCXA_MCXA366._lpadc_hardware_average_mode.kLPADC_HardwareAverageCount128 (*C enumerator*), 634
drivers_MCX_MCXA_MCXA366._lpadc_hardware_compare_mode (*C enum*), 634
drivers_MCX_MCXA_MCXA366._lpadc_hardware_compare_mode.kLPADC_HardwareCompareDisabled (*C enumerator*), 635
drivers_MCX_MCXA_MCXA366._lpadc_hardware_compare_mode.kLPADC_HardwareCompareRepeatUntilTrue (*C enumerator*), 635
drivers_MCX_MCXA_MCXA366._lpadc_hardware_compare_mode.kLPADC_HardwareCompareStoreOnTrue (*C enumerator*), 635
drivers_MCX_MCXA_MCXA366._lpadc_interrupt_enable (*C enum*), 631
drivers_MCX_MCXA_MCXA366._lpadc_interrupt_enable.kLPADC_FIFO0WatermarkInterruptEnable (*C enumerator*), 631
drivers_MCX_MCXA_MCXA366._lpadc_interrupt_enable.kLPADC_FIFOWatermarkInterruptEnable (*C enumerator*), 631
drivers_MCX_MCXA_MCXA366._lpadc_interrupt_enable.kLPADC_ResultFIFO0OverflowInterruptEnable (*C enumerator*), 631
drivers_MCX_MCXA_MCXA366._lpadc_interrupt_enable.kLPADC_ResultFIFOOverflowInterruptEnable (*C enumerator*), 631
drivers_MCX_MCXA_MCXA366._lpadc_interrupt_enable.kLPADC_Trigger0CompletionInterruptEnable (*C enumerator*), 632
drivers_MCX_MCXA_MCXA366._lpadc_interrupt_enable.kLPADC_Trigger1CompletionInterruptEnable (*C enumerator*), 632
drivers_MCX_MCXA_MCXA366._lpadc_interrupt_enable.kLPADC_TriggerExceptionInterruptEnable (*C enumerator*), 632
drivers_MCX_MCXA_MCXA366._lpadc_offset_calibration_mode (*C enum*), 636
drivers_MCX_MCXA_MCXA366._lpadc_offset_calibration_mode.kLPADC_OffsetCalibration12bitMode (*C enumerator*), 637
drivers_MCX_MCXA_MCXA366._lpadc_offset_calibration_mode.kLPADC_OffsetCalibration16bitMode (*C enumerator*), 637
drivers_MCX_MCXA_MCXA366._lpadc_power_level_mode (*C enum*), 636
drivers_MCX_MCXA_MCXA366._lpadc_power_level_mode.kLPADC_PowerLevelAlt1 (*C enumerator*), 636
drivers_MCX_MCXA_MCXA366._lpadc_power_level_mode.kLPADC_PowerLevelAlt2 (*C enumerator*), 636
drivers_MCX_MCXA_MCXA366._lpadc_power_level_mode.kLPADC_PowerLevelAlt3 (*C enumerator*), 636
drivers_MCX_MCXA_MCXA366._lpadc_power_level_mode.kLPADC_PowerLevelAlt4 (*C enumerator*), 636
drivers_MCX_MCXA_MCXA366._lpadc_reference_voltage_mode (*C enum*), 636
drivers_MCX_MCXA_MCXA366._lpadc_reference_voltage_mode.kLPADC_ReferenceVoltageAlt1 (*C enumerator*), 636
drivers_MCX_MCXA_MCXA366._lpadc_reference_voltage_mode.kLPADC_ReferenceVoltageAlt2 (*C enumerator*), 636
drivers_MCX_MCXA_MCXA366._lpadc_reference_voltage_mode.kLPADC_ReferenceVoltageAlt3 (*C enumerator*), 636
drivers_MCX_MCXA_MCXA366._lpadc_sample_channel_mode (*C enum*), 632
drivers_MCX_MCXA_MCXA366._lpadc_sample_channel_mode.kLPADC_SampleChannelDiffBothSide (*C enumerator*), 633
drivers_MCX_MCXA_MCXA366._lpadc_sample_channel_mode.kLPADC_SampleChannelDiffBothSideAB (*C enumerator*), 633
drivers_MCX_MCXA_MCXA366._lpadc_sample_channel_mode.kLPADC_SampleChannelDiffBothSideBA (*C enumerator*), 633
drivers_MCX_MCXA_MCXA366._lpadc_sample_channel_mode.kLPADC_SampleChannelDualSingleEndBothSide (*C enumerator*), 633
drivers_MCX_MCXA_MCXA366._lpadc_sample_channel_mode.kLPADC_SampleChannelSingleEndSideA (*C enumerator*), 633
drivers_MCX_MCXA_MCXA366._lpadc_sample_channel_mode.kLPADC_SampleChannelSingleEndSideB (*C enumerator*), 633

drivers_MCX_MCXA_MCXA366._lpadc_sample_scale_mode (*C enum*), 632
drivers_MCX_MCXA_MCXA366._lpadc_sample_scale_mode.kLPADC_SampleFullScale (*C enumerator*), 632
drivers_MCX_MCXA_MCXA366._lpadc_sample_scale_mode.kLPADC_SamplePartScale (*C enumerator*), 632
drivers_MCX_MCXA_MCXA366._lpadc_sample_time_mode (*C enum*), 634
drivers_MCX_MCXA_MCXA366._lpadc_sample_time_mode.kLPADC_SampleTimeADCK3 (*C enumerator*), 634
drivers_MCX_MCXA_MCXA366._lpadc_sample_time_mode.kLPADC_SampleTimeADCK5 (*C enumerator*), 634
drivers_MCX_MCXA_MCXA366._lpadc_sample_time_mode.kLPADC_SampleTimeADCK7 (*C enumerator*), 634
drivers_MCX_MCXA_MCXA366._lpadc_sample_time_mode.kLPADC_SampleTimeADCK11 (*C enumerator*), 634
drivers_MCX_MCXA_MCXA366._lpadc_sample_time_mode.kLPADC_SampleTimeADCK19 (*C enumerator*), 634
drivers_MCX_MCXA_MCXA366._lpadc_sample_time_mode.kLPADC_SampleTimeADCK35 (*C enumerator*), 634
drivers_MCX_MCXA_MCXA366._lpadc_sample_time_mode.kLPADC_SampleTimeADCK67 (*C enumerator*), 634
drivers_MCX_MCXA_MCXA366._lpadc_sample_time_mode.kLPADC_SampleTimeADCK131 (*C enumerator*), 634
drivers_MCX_MCXA_MCXA366._lpadc_status_flags (*C enum*), 631
drivers_MCX_MCXA_MCXA366._lpadc_status_flags.kLPADC_ActiveFlag (*C enumerator*), 631
drivers_MCX_MCXA_MCXA366._lpadc_status_flags.kLPADC_CalibrationReadyFlag (*C enumerator*), 631
drivers_MCX_MCXA_MCXA366._lpadc_status_flags.kLPADC_ResultFIFO0OverflowFlag (*C enumerator*), 631
drivers_MCX_MCXA_MCXA366._lpadc_status_flags.kLPADC_ResultFIFO0ReadyFlag (*C enumerator*), 631
drivers_MCX_MCXA_MCXA366._lpadc_status_flags.kLPADC_ResultFIFOOverflowFlag (*C enumerator*), 631
drivers_MCX_MCXA_MCXA366._lpadc_status_flags.kLPADC_ResultFIFOReadyFlag (*C enumerator*), 631
drivers_MCX_MCXA_MCXA366._lpadc_status_flags.kLPADC_TriggerCompletionFlag (*C enumerator*), 631
drivers_MCX_MCXA_MCXA366._lpadc_status_flags.kLPADC_TriggerExceptionFlag (*C enumerator*), 631
drivers_MCX_MCXA_MCXA366._lpadc_trigger_priority_policy (*C enum*), 637
drivers_MCX_MCXA_MCXA366._lpadc_trigger_priority_policy.kLPADC_ConvPreemptImmediatelyAutoRestarted (*C enumerator*), 637
drivers_MCX_MCXA_MCXA366._lpadc_trigger_priority_policy.kLPADC_ConvPreemptImmediatelyAutoResumed (*C enumerator*), 637
drivers_MCX_MCXA_MCXA366._lpadc_trigger_priority_policy.kLPADC_ConvPreemptImmediatelyNotAutoResum (*C enumerator*), 637
drivers_MCX_MCXA_MCXA366._lpadc_trigger_priority_policy.kLPADC_ConvPreemptSoftlyAutoRestarted (*C enumerator*), 637
drivers_MCX_MCXA_MCXA366._lpadc_trigger_priority_policy.kLPADC_ConvPreemptSoftlyAutoResumed (*C enumerator*), 637
drivers_MCX_MCXA_MCXA366._lpadc_trigger_priority_policy.kLPADC_ConvPreemptSoftlyNotAutoResumed (*C enumerator*), 637
drivers_MCX_MCXA_MCXA366._lpadc_trigger_priority_policy.kLPADC_TriggerPriorityExceptionDisabled (*C enumerator*), 638
drivers_MCX_MCXA_MCXA366._lpadc_trigger_priority_policy.kLPADC_TriggerPriorityPreemptImmediately (*C enumerator*), 638
drivers_MCX_MCXA_MCXA366._lpadc_trigger_priority_policy.kLPADC_TriggerPriorityPreemptSoftly (*C enumerator*), 638
drivers_MCX_MCXA_MCXA366._lpadc_trigger_status_flags (*C enum*), 632

drivers_MCX_MCXA_MCXA366._lpadc_trigger_status_flags.kLPADC_Trigger0CompletedFlag (*C enumerator*), 632
drivers_MCX_MCXA_MCXA366._lpadc_trigger_status_flags.kLPADC_Trigger0InterruptedFlag (*C enumerator*), 632
drivers_MCX_MCXA_MCXA366._lpadc_trigger_status_flags.kLPADC_Trigger1CompletedFlag (*C enumerator*), 632
drivers_MCX_MCXA_MCXA366._lpadc_trigger_status_flags.kLPADC_Trigger1InterruptedFlag (*C enumerator*), 632
drivers_MCX_MCXA_MCXA366._lpadc_tune_value (*C enum*), 638
drivers_MCX_MCXA_MCXA366._lpadc_tune_value.kLPADC_TuneValue0 (*C enumerator*), 638
drivers_MCX_MCXA_MCXA366._lpadc_tune_value.kLPADC_TuneValue1 (*C enumerator*), 638
drivers_MCX_MCXA_MCXA366._lpadc_tune_value.kLPADC_TuneValue2 (*C enumerator*), 638
drivers_MCX_MCXA_MCXA366._lpadc_tune_value.kLPADC_TuneValue3 (*C enumerator*), 638
drivers_MCX_MCXA_MCXA366._lpcmp_close_window_event (*C enum*), 664
drivers_MCX_MCXA_MCXA366._lpcmp_close_window_event.kLPCMP_CLoseWindowEventBothEdge (*C enumerator*), 665
drivers_MCX_MCXA_MCXA366._lpcmp_close_window_event.kLPCMP_CloseWindowEventFallingEdge (*C enumerator*), 664
drivers_MCX_MCXA_MCXA366._lpcmp_close_window_event.kLPCMP_CLoseWindowEventNoSet (*C enumerator*), 664
drivers_MCX_MCXA_MCXA366._lpcmp_close_window_event.kLPCMP_CloseWindowEventRisingEdge (*C enumerator*), 664
drivers_MCX_MCXA_MCXA366._lpcmp_config (*C struct*), 668
drivers_MCX_MCXA_MCXA366._lpcmp_config.enableCmpToDacLink (*C var*), 668
drivers_MCX_MCXA_MCXA366._lpcmp_config.enableInvertOutput (*C var*), 668
drivers_MCX_MCXA_MCXA366._lpcmp_config.enableOutputPin (*C var*), 668
drivers_MCX_MCXA_MCXA366._lpcmp_config.enableStopMode (*C var*), 668
drivers_MCX_MCXA_MCXA366._lpcmp_config.functionalSourceClock (*C var*), 668
drivers_MCX_MCXA_MCXA366._lpcmp_config.hysteresisMode (*C var*), 668
drivers_MCX_MCXA_MCXA366._lpcmp_config.minusInputSrc (*C var*), 668
drivers_MCX_MCXA_MCXA366._lpcmp_config.plusInputSrc (*C var*), 668
drivers_MCX_MCXA_MCXA366._lpcmp_config.powerMode (*C var*), 668
drivers_MCX_MCXA_MCXA366._lpcmp_config.useUnfilteredOutput (*C var*), 668
drivers_MCX_MCXA_MCXA366._lpcmp_couta_signal (*C enum*), 664
drivers_MCX_MCXA_MCXA366._lpcmp_couta_signal.kLPCMP_COUTASignalHigh (*C enumerator*), 664
drivers_MCX_MCXA_MCXA366._lpcmp_couta_signal.kLPCMP_COUTASignalLow (*C enumerator*), 664
drivers_MCX_MCXA_MCXA366._lpcmp_couta_signal.kLPCMP_COUTASignalNoSet (*C enumerator*), 664
drivers_MCX_MCXA_MCXA366._lpcmp_dac_config (*C struct*), 667
drivers_MCX_MCXA_MCXA366._lpcmp_dac_config.DACValue (*C var*), 668
drivers_MCX_MCXA_MCXA366._lpcmp_dac_config.enableLowPowerMode (*C var*), 668
drivers_MCX_MCXA_MCXA366._lpcmp_dac_config.referenceVoltageSource (*C var*), 668
drivers_MCX_MCXA_MCXA366._lpcmp_dac_reference_voltage_source (*C enum*), 663
drivers_MCX_MCXA_MCXA366._lpcmp_dac_reference_voltage_source.kLPCMP_VrefSourceVin1 (*C enumerator*), 663
drivers_MCX_MCXA_MCXA366._lpcmp_dac_reference_voltage_source.kLPCMP_VrefSourceVin2 (*C enumerator*), 664
drivers_MCX_MCXA_MCXA366._lpcmp_filter_config (*C struct*), 667
drivers_MCX_MCXA_MCXA366._lpcmp_filter_config.enableSample (*C var*), 667
drivers_MCX_MCXA_MCXA366._lpcmp_filter_config.filterSampleCount (*C var*), 667
drivers_MCX_MCXA_MCXA366._lpcmp_filter_config.filterSamplePeriod (*C var*), 667
drivers_MCX_MCXA_MCXA366._lpcmp_functional_source_clock (*C enum*), 664
drivers_MCX_MCXA_MCXA366._lpcmp_functional_source_clock.kLPCMP_FunctionalClockSource0 (*C enumerator*), 664
drivers_MCX_MCXA_MCXA366._lpcmp_functional_source_clock.kLPCMP_FunctionalClockSource1 (*C enumerator*), 664

drivers_MCX_MCXA_MCXA366._lpcmp_functional_source_clock.kLPCMP_FunctionalClockSource2 (*C enumerator*), 664
drivers_MCX_MCXA_MCXA366._lpcmp_functional_source_clock.kLPCMP_FunctionalClockSource3 (*C enumerator*), 664
drivers_MCX_MCXA_MCXA366._lpcmp_hysteresis_mode (*C enum*), 663
drivers_MCX_MCXA_MCXA366._lpcmp_hysteresis_mode.kLPCMP_HysteresisLevel0 (*C enumerator*), 663
drivers_MCX_MCXA_MCXA366._lpcmp_hysteresis_mode.kLPCMP_HysteresisLevel1 (*C enumerator*), 663
drivers_MCX_MCXA_MCXA366._lpcmp_hysteresis_mode.kLPCMP_HysteresisLevel2 (*C enumerator*), 663
drivers_MCX_MCXA_MCXA366._lpcmp_hysteresis_mode.kLPCMP_HysteresisLevel3 (*C enumerator*), 663
drivers_MCX_MCXA_MCXA366._lpcmp_interrupt_enable (*C enum*), 662
drivers_MCX_MCXA_MCXA366._lpcmp_interrupt_enable.kLPCMP_OutputFallingInterruptEnable (*C enumerator*), 663
drivers_MCX_MCXA_MCXA366._lpcmp_interrupt_enable.kLPCMP_OutputRisingInterruptEnable (*C enumerator*), 663
drivers_MCX_MCXA_MCXA366._lpcmp_interrupt_enable.kLPCMP_RoundRobinInterruptEnable (*C enumerator*), 663
drivers_MCX_MCXA_MCXA366._lpcmp_minus_input_src (*C enum*), 666
drivers_MCX_MCXA_MCXA366._lpcmp_minus_input_src.kLPCMP_MinusInputSrcDac (*C enumerator*), 666
drivers_MCX_MCXA_MCXA366._lpcmp_minus_input_src.kLPCMP_MinusInputSrcMux (*C enumerator*), 666
drivers_MCX_MCXA_MCXA366._lpcmp_plus_input_src (*C enum*), 665
drivers_MCX_MCXA_MCXA366._lpcmp_plus_input_src.kLPCMP_PlusInputSrcDac (*C enumerator*), 665
drivers_MCX_MCXA_MCXA366._lpcmp_plus_input_src.kLPCMP_PlusInputSrcMux (*C enumerator*), 666
drivers_MCX_MCXA_MCXA366._lpcmp_power_mode (*C enum*), 663
drivers_MCX_MCXA_MCXA366._lpcmp_power_mode.kLPCMP_HighSpeedPowerMode (*C enumerator*), 663
drivers_MCX_MCXA_MCXA366._lpcmp_power_mode.kLPCMP_LowSpeedPowerMode (*C enumerator*), 663
drivers_MCX_MCXA_MCXA366._lpcmp_power_mode.kLPCMP_NanoPowerMode (*C enumerator*), 663
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_clock_source (*C enum*), 665
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_clock_source.kLPCMP_RoundRobinClockSource0 (*C enumerator*), 665
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_clock_source.kLPCMP_RoundRobinClockSource1 (*C enumerator*), 665
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_clock_source.kLPCMP_RoundRobinClockSource2 (*C enumerator*), 665
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_clock_source.kLPCMP_RoundRobinClockSource3 (*C enumerator*), 665
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_config (*C struct*), 669
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_config.channelSampleNumbers (*C var*), 669
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_config.checkerChannelMask (*C var*), 670
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_config.fixedChannel (*C var*), 669
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_config.fixedMuxPort (*C var*), 669
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_config.initDelayModules (*C var*), 669
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_config.roundrobinClockSource (*C var*), 669
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_config.roundrobinTriggerSource (*C var*), 669
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_config.sampleClockNumbers (*C var*), 669
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_config.sampleTimeThreshhold (*C var*), 669
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_fixedmuxport (*C enum*), 665
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_fixedmuxport.kLPCMP_FixedMinusMuxPort

(*C enumerator*), 665
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_fixedmuxport.kLPCMP_FixedPlusMuxPort (*C enumerator*), 665
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_trigger_source (*C enum*), 665
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_trigger_source.kLPCMP_TriggerSourceExternally (*C enumerator*), 665
drivers_MCX_MCXA_MCXA366._lpcmp_roundrobin_trigger_source.kLPCMP_TriggerSourceInternally (*C enumerator*), 665
drivers_MCX_MCXA_MCXA366._lpcmp_status_flags (*C enum*), 662
drivers_MCX_MCXA_MCXA366._lpcmp_status_flags.kLPCMP_OutputAssertEventFlag (*C enumerator*), 662
drivers_MCX_MCXA_MCXA366._lpcmp_status_flags.kLPCMP_OutputFallingEventFlag (*C enumerator*), 662
drivers_MCX_MCXA_MCXA366._lpcmp_status_flags.kLPCMP_OutputRisingEventFlag (*C enumerator*), 662
drivers_MCX_MCXA_MCXA366._lpcmp_status_flags.kLPCMP_OutputRoundRobinEventFlag (*C enumerator*), 662
drivers_MCX_MCXA_MCXA366._lpcmp_window_control_config (*C struct*), 669
drivers_MCX_MCXA_MCXA366._lpcmp_window_control_config.closeWindowEvent (*C var*), 669
drivers_MCX_MCXA_MCXA366._lpcmp_window_control_config.COUTASignal (*C var*), 669
drivers_MCX_MCXA_MCXA366._lpcmp_window_control_config.enableInvertWindowSignal (*C var*), 669
drivers_MCX_MCXA_MCXA366._lpi2c_data_match_config_mode (*C enum*), 682
drivers_MCX_MCXA_MCXA366._lpi2c_data_match_config_mode.kLPI2C_1stWordAndM1EqualsM0AndM1 (*C enumerator*), 682
drivers_MCX_MCXA_MCXA366._lpi2c_data_match_config_mode.kLPI2C_1stWordEqualsM0And2ndWordEqualsM (*C enumerator*), 682
drivers_MCX_MCXA_MCXA366._lpi2c_data_match_config_mode.kLPI2C_1stWordEqualsM0OrM1 (*C enumerator*), 682
drivers_MCX_MCXA_MCXA366._lpi2c_data_match_config_mode.kLPI2C_AnyWordAndM1EqualsM0AndM1 (*C enumerator*), 682
drivers_MCX_MCXA_MCXA366._lpi2c_data_match_config_mode.kLPI2C_AnyWordEqualsM0AndNextWordEqua (*C enumerator*), 682
drivers_MCX_MCXA_MCXA366._lpi2c_data_match_config_mode.kLPI2C_AnyWordEqualsM0OrM1 (*C enumerator*), 682
drivers_MCX_MCXA_MCXA366._lpi2c_data_match_config_mode.kLPI2C_MatchDisabled (*C enumerator*), 682
drivers_MCX_MCXA_MCXA366._lpi2c_direction (*C enum*), 681
drivers_MCX_MCXA_MCXA366._lpi2c_direction.kLPI2C_Read (*C enumerator*), 681
drivers_MCX_MCXA_MCXA366._lpi2c_direction.kLPI2C_Write (*C enumerator*), 681
drivers_MCX_MCXA_MCXA366._lpi2c_host_request_polarity (*C enum*), 682
drivers_MCX_MCXA_MCXA366._lpi2c_host_request_polarity.kLPI2C_HostRequestPinActiveHigh (*C enumerator*), 682
drivers_MCX_MCXA_MCXA366._lpi2c_host_request_polarity.kLPI2C_HostRequestPinActiveLow (*C enumerator*), 682
drivers_MCX_MCXA_MCXA366._lpi2c_host_request_source (*C enum*), 682
drivers_MCX_MCXA_MCXA366._lpi2c_host_request_source.kLPI2C_HostRequestExternalPin (*C enumerator*), 682
drivers_MCX_MCXA_MCXA366._lpi2c_host_request_source.kLPI2C_HostRequestInputTrigger (*C enumerator*), 682
drivers_MCX_MCXA_MCXA366._lpi2c_master_config (*C struct*), 684
drivers_MCX_MCXA_MCXA366._lpi2c_master_config.baudRate_Hz (*C var*), 684
drivers_MCX_MCXA_MCXA366._lpi2c_master_config.busIdleTimeout_ns (*C var*), 684
drivers_MCX_MCXA_MCXA366._lpi2c_master_config.debugEnable (*C var*), 684
drivers_MCX_MCXA_MCXA366._lpi2c_master_config.enableDoze (*C var*), 684
drivers_MCX_MCXA_MCXA366._lpi2c_master_config.enableMaster (*C var*), 684
drivers_MCX_MCXA_MCXA366._lpi2c_master_config.hostRequest (*C struct*), 686
drivers_MCX_MCXA_MCXA366._lpi2c_master_config.hostRequest (*C var*), 685

drivers_MCX_MCXA_MCXA366._lpi2c_master_config.hostRequest.enable (*C var*), 687
drivers_MCX_MCXA_MCXA366._lpi2c_master_config.hostRequest.polarity (*C var*), 687
drivers_MCX_MCXA_MCXA366._lpi2c_master_config.hostRequest.source (*C var*), 687
drivers_MCX_MCXA_MCXA366._lpi2c_master_config.ignoreAck (*C var*), 684
drivers_MCX_MCXA_MCXA366._lpi2c_master_config.pinConfig (*C var*), 684
drivers_MCX_MCXA_MCXA366._lpi2c_master_config.pinLowTimeout_ns (*C var*), 685
drivers_MCX_MCXA_MCXA366._lpi2c_master_config.sclGlitchFilterWidth_ns (*C var*), 685
drivers_MCX_MCXA_MCXA366._lpi2c_master_config.sdaGlitchFilterWidth_ns (*C var*), 685
drivers_MCX_MCXA_MCXA366._lpi2c_master_edma_handle (*C struct*), 689
drivers_MCX_MCXA_MCXA366._lpi2c_master_edma_handle.base (*C var*), 689
drivers_MCX_MCXA_MCXA366._lpi2c_master_edma_handle.commandBuffer (*C var*), 689
drivers_MCX_MCXA_MCXA366._lpi2c_master_edma_handle.completionCallback (*C var*), 689
drivers_MCX_MCXA_MCXA366._lpi2c_master_edma_handle.isBusy (*C var*), 689
drivers_MCX_MCXA_MCXA366._lpi2c_master_edma_handle.nbytes (*C var*), 689
drivers_MCX_MCXA_MCXA366._lpi2c_master_edma_handle.rx (*C var*), 689
drivers_MCX_MCXA_MCXA366._lpi2c_master_edma_handle.tcds (*C var*), 689
drivers_MCX_MCXA_MCXA366._lpi2c_master_edma_handle.transfer (*C var*), 689
drivers_MCX_MCXA_MCXA366._lpi2c_master_edma_handle.tx (*C var*), 689
drivers_MCX_MCXA_MCXA366._lpi2c_master_edma_handle.userData (*C var*), 689
drivers_MCX_MCXA_MCXA366._lpi2c_master_flags (*C enum*), 679
drivers_MCX_MCXA_MCXA366._lpi2c_master_flags.kLPI2C_MasterArbitrationLostFlag (*C enumerator*), 680
drivers_MCX_MCXA_MCXA366._lpi2c_master_flags.kLPI2C_MasterBusBusyFlag (*C enumerator*), 680
drivers_MCX_MCXA_MCXA366._lpi2c_master_flags.kLPI2C_MasterBusyFlag (*C enumerator*), 680
drivers_MCX_MCXA_MCXA366._lpi2c_master_flags.kLPI2C_MasterClearFlags (*C enumerator*), 681
drivers_MCX_MCXA_MCXA366._lpi2c_master_flags.kLPI2C_MasterDataMatchFlag (*C enumerator*), 680
drivers_MCX_MCXA_MCXA366._lpi2c_master_flags.kLPI2C_MasterEndOfPacketFlag (*C enumerator*), 680
drivers_MCX_MCXA_MCXA366._lpi2c_master_flags.kLPI2C_MasterErrorFlags (*C enumerator*), 681
drivers_MCX_MCXA_MCXA366._lpi2c_master_flags.kLPI2C_MasterFifoErrFlag (*C enumerator*), 680
drivers_MCX_MCXA_MCXA366._lpi2c_master_flags.kLPI2C_MasterIrqFlags (*C enumerator*), 681
drivers_MCX_MCXA_MCXA366._lpi2c_master_flags.kLPI2C_MasterNackDetectFlag (*C enumerator*), 680
drivers_MCX_MCXA_MCXA366._lpi2c_master_flags.kLPI2C_MasterPinLowTimeoutFlag (*C enumerator*), 680
drivers_MCX_MCXA_MCXA366._lpi2c_master_flags.kLPI2C_MasterRxReadyFlag (*C enumerator*), 680
drivers_MCX_MCXA_MCXA366._lpi2c_master_flags.kLPI2C_MasterStopDetectFlag (*C enumerator*), 680
drivers_MCX_MCXA_MCXA366._lpi2c_master_flags.kLPI2C_MasterTxReadyFlag (*C enumerator*), 680
drivers_MCX_MCXA_MCXA366._lpi2c_master_handle (*C struct*), 686
drivers_MCX_MCXA_MCXA366._lpi2c_master_handle.buf (*C var*), 686
drivers_MCX_MCXA_MCXA366._lpi2c_master_handle.chunkSize (*C var*), 686
drivers_MCX_MCXA_MCXA366._lpi2c_master_handle.commandBuffer (*C var*), 686
drivers_MCX_MCXA_MCXA366._lpi2c_master_handle.completionCallback (*C var*), 686
drivers_MCX_MCXA_MCXA366._lpi2c_master_handle.remainingBytes (*C var*), 686
drivers_MCX_MCXA_MCXA366._lpi2c_master_handle.state (*C var*), 686
drivers_MCX_MCXA_MCXA366._lpi2c_master_handle.transfer (*C var*), 686
drivers_MCX_MCXA_MCXA366._lpi2c_master_handle.userData (*C var*), 686
drivers_MCX_MCXA_MCXA366._lpi2c_master_pin_config (*C enum*), 681

drivers_MCX_MCXA_MCXA366._lpi2c_master_pin_config.kLPI2C_2PinOpenDrain (*C enumerator*), 681
drivers_MCX_MCXA_MCXA366._lpi2c_master_pin_config.kLPI2C_2PinOpenDrainWithSeparateSlave (*C enumerator*), 681
drivers_MCX_MCXA_MCXA366._lpi2c_master_pin_config.kLPI2C_2PinOutputOnly (*C enumerator*), 681
drivers_MCX_MCXA_MCXA366._lpi2c_master_pin_config.kLPI2C_2PinOutputOnlyWithSeparateSlave (*C enumerator*), 681
drivers_MCX_MCXA_MCXA366._lpi2c_master_pin_config.kLPI2C_2PinPushPull (*C enumerator*), 681
drivers_MCX_MCXA_MCXA366._lpi2c_master_pin_config.kLPI2C_2PinPushPullWithSeparateSlave (*C enumerator*), 681
drivers_MCX_MCXA_MCXA366._lpi2c_master_pin_config.kLPI2C_4PinPushPull (*C enumerator*), 681
drivers_MCX_MCXA_MCXA366._lpi2c_master_pin_config.kLPI2C_4PinPushPullWithInvertedOutput (*C enumerator*), 681
drivers_MCX_MCXA_MCXA366._lpi2c_master_transfer (*C struct*), 685
drivers_MCX_MCXA_MCXA366._lpi2c_master_transfer_flags (*C enum*), 682
drivers_MCX_MCXA_MCXA366._lpi2c_master_transfer_flags.kLPI2C_TransferDefaultFlag (*C enumerator*), 683
drivers_MCX_MCXA_MCXA366._lpi2c_master_transfer_flags.kLPI2C_TransferNoStartFlag (*C enumerator*), 683
drivers_MCX_MCXA_MCXA366._lpi2c_master_transfer_flags.kLPI2C_TransferNoStopFlag (*C enumerator*), 683
drivers_MCX_MCXA_MCXA366._lpi2c_master_transfer.data (*C var*), 686
drivers_MCX_MCXA_MCXA366._lpi2c_master_transfer.dataSize (*C var*), 686
drivers_MCX_MCXA_MCXA366._lpi2c_master_transfer.direction (*C var*), 685
drivers_MCX_MCXA_MCXA366._lpi2c_master_transfer.flags (*C var*), 685
drivers_MCX_MCXA_MCXA366._lpi2c_master_transfer.slaveAddress (*C var*), 685
drivers_MCX_MCXA_MCXA366._lpi2c_master_transfer.subaddress (*C var*), 686
drivers_MCX_MCXA_MCXA366._lpi2c_master_transfer.subaddressSize (*C var*), 686
drivers_MCX_MCXA_MCXA366._lpi2c_match_config (*C struct*), 685
drivers_MCX_MCXA_MCXA366._lpi2c_match_config.match0 (*C var*), 685
drivers_MCX_MCXA_MCXA366._lpi2c_match_config.match1 (*C var*), 685
drivers_MCX_MCXA_MCXA366._lpi2c_match_config.matchMode (*C var*), 685
drivers_MCX_MCXA_MCXA366._lpi2c_match_config.rxDataMatchOnly (*C var*), 685
drivers_MCX_MCXA_MCXA366._lpi2c_slave_address_match (*C enum*), 696
drivers_MCX_MCXA_MCXA366._lpi2c_slave_address_match.kLPI2C_MatchAddress0 (*C enumerator*), 696
drivers_MCX_MCXA_MCXA366._lpi2c_slave_address_match.kLPI2C_MatchAddress0OrAddress1 (*C enumerator*), 696
drivers_MCX_MCXA_MCXA366._lpi2c_slave_address_match.kLPI2C_MatchAddress0ThroughAddress1 (*C enumerator*), 696
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config (*C struct*), 698
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.address0 (*C var*), 698
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.address1 (*C var*), 698
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.addressMatchMode (*C var*), 698
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.clockHoldTime_ns (*C var*), 699
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.dataValidDelay_ns (*C var*), 699
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.enableGeneralCall (*C var*), 699
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.enableReceivedAddressRead (*C var*), 699
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.enableSlave (*C var*), 698
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.filterDozeEnable (*C var*), 698
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.filterEnable (*C var*), 699
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.ignoreAck (*C var*), 699
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.sclGlitchFilterWidth_ns (*C var*), 699
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.sclStall (*C struct*), 700
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.sclStall (*C var*), 699

drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.sclStall.enableAck (*C var*), 700
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.sclStall.enableAddress (*C var*), 701
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.sclStall.enableRx (*C var*), 701
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.sclStall.enableTx (*C var*), 700
drivers_MCX_MCXA_MCXA366._lpi2c_slave_config.sdaGlitchFilterWidth_ns (*C var*), 699
drivers_MCX_MCXA_MCXA366._lpi2c_slave_flags (*C enum*), 695
drivers_MCX_MCXA_MCXA366._lpi2c_slave_flags.kLPI2C_SlaveAddressMatch0Flag (*C enumerator*), 696
drivers_MCX_MCXA_MCXA366._lpi2c_slave_flags.kLPI2C_SlaveAddressMatch1Flag (*C enumerator*), 696
drivers_MCX_MCXA_MCXA366._lpi2c_slave_flags.kLPI2C_SlaveAddressValidFlag (*C enumerator*), 695
drivers_MCX_MCXA_MCXA366._lpi2c_slave_flags.kLPI2C_SlaveBitErrFlag (*C enumerator*), 696
drivers_MCX_MCXA_MCXA366._lpi2c_slave_flags.kLPI2C_SlaveBusBusyFlag (*C enumerator*), 696
drivers_MCX_MCXA_MCXA366._lpi2c_slave_flags.kLPI2C_SlaveBusyFlag (*C enumerator*), 696
drivers_MCX_MCXA_MCXA366._lpi2c_slave_flags.kLPI2C_SlaveClearFlags (*C enumerator*), 696
drivers_MCX_MCXA_MCXA366._lpi2c_slave_flags.kLPI2C_SlaveErrorFlags (*C enumerator*), 696
drivers_MCX_MCXA_MCXA366._lpi2c_slave_flags.kLPI2C_SlaveFifoErrFlag (*C enumerator*), 696
drivers_MCX_MCXA_MCXA366._lpi2c_slave_flags.kLPI2C_SlaveGeneralCallFlag (*C enumerator*), 696
drivers_MCX_MCXA_MCXA366._lpi2c_slave_flags.kLPI2C_SlaveIrqFlags (*C enumerator*), 696
drivers_MCX_MCXA_MCXA366._lpi2c_slave_flags.kLPI2C_SlaveRepeatedStartDetectFlag (*C enumerator*), 696
drivers_MCX_MCXA_MCXA366._lpi2c_slave_flags.kLPI2C_SlaveRxReadyFlag (*C enumerator*), 695
drivers_MCX_MCXA_MCXA366._lpi2c_slave_flags.kLPI2C_SlaveStopDetectFlag (*C enumerator*), 696
drivers_MCX_MCXA_MCXA366._lpi2c_slave_flags.kLPI2C_SlaveTransmitAckFlag (*C enumerator*), 695
drivers_MCX_MCXA_MCXA366._lpi2c_slave_flags.kLPI2C_SlaveTxReadyFlag (*C enumerator*), 695
drivers_MCX_MCXA_MCXA366._lpi2c_slave_handle (*C struct*), 700
drivers_MCX_MCXA_MCXA366._lpi2c_slave_handle.callback (*C var*), 700
drivers_MCX_MCXA_MCXA366._lpi2c_slave_handle.eventMask (*C var*), 700
drivers_MCX_MCXA_MCXA366._lpi2c_slave_handle.isBusy (*C var*), 700
drivers_MCX_MCXA_MCXA366._lpi2c_slave_handle.transfer (*C var*), 700
drivers_MCX_MCXA_MCXA366._lpi2c_slave_handle.transferredCount (*C var*), 700
drivers_MCX_MCXA_MCXA366._lpi2c_slave_handle.userData (*C var*), 700
drivers_MCX_MCXA_MCXA366._lpi2c_slave_handle.wasTransmit (*C var*), 700
drivers_MCX_MCXA_MCXA366._lpi2c_slave_transfer (*C struct*), 699
drivers_MCX_MCXA_MCXA366._lpi2c_slave_transfer_event (*C enum*), 697
drivers_MCX_MCXA_MCXA366._lpi2c_slave_transfer_event.kLPI2C_SlaveAddressMatchEvent (*C enumerator*), 697
drivers_MCX_MCXA_MCXA366._lpi2c_slave_transfer_event.kLPI2C_SlaveAllEvents (*C enumerator*), 697
drivers_MCX_MCXA_MCXA366._lpi2c_slave_transfer_event.kLPI2C_SlaveCompletionEvent (*C enumerator*), 697
drivers_MCX_MCXA_MCXA366._lpi2c_slave_transfer_event.kLPI2C_SlaveReceiveEvent (*C enumerator*), 697
drivers_MCX_MCXA_MCXA366._lpi2c_slave_transfer_event.kLPI2C_SlaveRepeatedStartEvent (*C enumerator*), 697
drivers_MCX_MCXA_MCXA366._lpi2c_slave_transfer_event.kLPI2C_SlaveTransmitAckEvent (*C enumerator*), 697
drivers_MCX_MCXA_MCXA366._lpi2c_slave_transfer_event.kLPI2C_SlaveTransmitEvent (*C enumerator*), 697
drivers_MCX_MCXA_MCXA366._lpi2c_slave_transfer.completionStatus (*C var*), 699
drivers_MCX_MCXA_MCXA366._lpi2c_slave_transfer.data (*C var*), 699

drivers_MCX_MCXA_MCXA366._lpi2c_slave_transfer.dataSize (*C var*), 699
drivers_MCX_MCXA_MCXA366._lpi2c_slave_transfer.event (*C var*), 699
drivers_MCX_MCXA_MCXA366._lpi2c_slave_transfer.receivedAddress (*C var*), 699
drivers_MCX_MCXA_MCXA366._lpi2c_slave_transfer.transferredCount (*C var*), 700
drivers_MCX_MCXA_MCXA366._lpspi_clock_phase (*C enum*), 715
drivers_MCX_MCXA_MCXA366._lpspi_clock_phase.kLPSPI_ClockPhaseFirstEdge (*C enumerator*), 715
drivers_MCX_MCXA_MCXA366._lpspi_clock_phase.kLPSPI_ClockPhaseSecondEdge (*C enumerator*), 715
drivers_MCX_MCXA_MCXA366._lpspi_clock_polarity (*C enum*), 714
drivers_MCX_MCXA_MCXA366._lpspi_clock_polarity.kLPSPI_ClockPolarityActiveHigh (*C enumerator*), 714
drivers_MCX_MCXA_MCXA366._lpspi_clock_polarity.kLPSPI_ClockPolarityActiveLow (*C enumerator*), 715
drivers_MCX_MCXA_MCXA366._lpspi_data_out_config (*C enum*), 716
drivers_MCX_MCXA_MCXA366._lpspi_data_out_config.kLpspiDataOutRetained (*C enumerator*), 716
drivers_MCX_MCXA_MCXA366._lpspi_data_out_config.kLpspiDataOutTristate (*C enumerator*), 716
drivers_MCX_MCXA_MCXA366._lpspi_delay_type (*C enum*), 717
drivers_MCX_MCXA_MCXA366._lpspi_delay_type.kLPSPI_BetweenTransfer (*C enumerator*), 717
drivers_MCX_MCXA_MCXA366._lpspi_delay_type.kLPSPI_LastSckToPcs (*C enumerator*), 717
drivers_MCX_MCXA_MCXA366._lpspi_delay_type.kLPSPI_PcsToSck (*C enumerator*), 717
drivers_MCX_MCXA_MCXA366._lpspi_dma_enable (*C enum*), 713
drivers_MCX_MCXA_MCXA366._lpspi_dma_enable.kLPSPI_RxDmaEnable (*C enumerator*), 713
drivers_MCX_MCXA_MCXA366._lpspi_dma_enable.kLPSPI_TxDmaEnable (*C enumerator*), 713
drivers_MCX_MCXA_MCXA366._lpspi_flags (*C enum*), 712
drivers_MCX_MCXA_MCXA366._lpspi_flags.kLPSPI_AllStatusFlag (*C enumerator*), 712
drivers_MCX_MCXA_MCXA366._lpspi_flags.kLPSPI_DataMatchFlag (*C enumerator*), 712
drivers_MCX_MCXA_MCXA366._lpspi_flags.kLPSPI_FrameCompleteFlag (*C enumerator*), 712
drivers_MCX_MCXA_MCXA366._lpspi_flags.kLPSPI_ModuleBusyFlag (*C enumerator*), 712
drivers_MCX_MCXA_MCXA366._lpspi_flags.kLPSPI_ReceiveErrorFlag (*C enumerator*), 712
drivers_MCX_MCXA_MCXA366._lpspi_flags.kLPSPI_RxDataReadyFlag (*C enumerator*), 712
drivers_MCX_MCXA_MCXA366._lpspi_flags.kLPSPI_TransferCompleteFlag (*C enumerator*), 712
drivers_MCX_MCXA_MCXA366._lpspi_flags.kLPSPI_TransmitErrorFlag (*C enumerator*), 712
drivers_MCX_MCXA_MCXA366._lpspi_flags.kLPSPI_TxDataRequestFlag (*C enumerator*), 712
drivers_MCX_MCXA_MCXA366._lpspi_flags.kLPSPI_WordCompleteFlag (*C enumerator*), 712
drivers_MCX_MCXA_MCXA366._lpspi_host_request_select (*C enum*), 715
drivers_MCX_MCXA_MCXA366._lpspi_host_request_select.kLPSPI_HostReqExtPin (*C enumerator*), 715
drivers_MCX_MCXA_MCXA366._lpspi_host_request_select.kLPSPI_HostReqInternalTrigger (*C enumerator*), 715
drivers_MCX_MCXA_MCXA366._lpspi_interrupt_enable (*C enum*), 712
drivers_MCX_MCXA_MCXA366._lpspi_interrupt_enable.kLPSPI_AllInterruptEnable (*C enumerator*), 713
drivers_MCX_MCXA_MCXA366._lpspi_interrupt_enable.kLPSPI_DataMatchInterruptEnable (*C enumerator*), 713
drivers_MCX_MCXA_MCXA366._lpspi_interrupt_enable.kLPSPI_FrameCompleteInterruptEnable (*C enumerator*), 713
drivers_MCX_MCXA_MCXA366._lpspi_interrupt_enable.kLPSPI_ReceiveErrorInterruptEnable (*C enumerator*), 713
drivers_MCX_MCXA_MCXA366._lpspi_interrupt_enable.kLPSPI_RxInterruptEnable (*C enumerator*), 713
drivers_MCX_MCXA_MCXA366._lpspi_interrupt_enable.kLPSPI_TransferCompleteInterruptEnable (*C enumerator*), 713
drivers_MCX_MCXA_MCXA366._lpspi_interrupt_enable.kLPSPI_TransmitErrorInterruptEnable (*C enumerator*), 713

drivers_MCX_MCXA_MCXA366._lpspi_interrupt_enable.kLPSPI_TxInterruptEnable (*C enumerator*), 712
drivers_MCX_MCXA_MCXA366._lpspi_interrupt_enable.kLPSPI_WordCompleteInterruptEnable (*C enumerator*), 713
drivers_MCX_MCXA_MCXA366._lpspi_master_config (*C struct*), 720
drivers_MCX_MCXA_MCXA366._lpspi_master_config.baudRate (*C var*), 720
drivers_MCX_MCXA_MCXA366._lpspi_master_config.betweenTransferDelayInNanoSec (*C var*), 721
drivers_MCX_MCXA_MCXA366._lpspi_master_config.bitsPerFrame (*C var*), 721
drivers_MCX_MCXA_MCXA366._lpspi_master_config.cpha (*C var*), 721
drivers_MCX_MCXA_MCXA366._lpspi_master_config.cpol (*C var*), 721
drivers_MCX_MCXA_MCXA366._lpspi_master_config.dataOutConfig (*C var*), 721
drivers_MCX_MCXA_MCXA366._lpspi_master_config.direction (*C var*), 721
drivers_MCX_MCXA_MCXA366._lpspi_master_config.enableInputDelay (*C var*), 721
drivers_MCX_MCXA_MCXA366._lpspi_master_config.lastSckToPcsDelayInNanoSec (*C var*), 721
drivers_MCX_MCXA_MCXA366._lpspi_master_config.pcsActiveHighOrLow (*C var*), 721
drivers_MCX_MCXA_MCXA366._lpspi_master_config.pcsToSckDelayInNanoSec (*C var*), 721
drivers_MCX_MCXA_MCXA366._lpspi_master_config.pinCfg (*C var*), 721
drivers_MCX_MCXA_MCXA366._lpspi_master_config.whichPcs (*C var*), 721
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle (*C struct*), 729
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.bytesEachRead (*C var*), 730
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.bytesEachWrite (*C var*), 729
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.bytesLastRead (*C var*), 730
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.callback (*C var*), 731
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.dataBytesEveryTime (*C var*), 730
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.dmaTransmitTime (*C var*), 730
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.edmaRxRegToRxDataHandle (*C var*), 731
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.edmaTxDataToTxRegHandle (*C var*), 731
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.fifoSize (*C var*), 729
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.isByteSwap (*C var*), 729
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.isMultiDMATransmit (*C var*), 730
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.isPcsContinuous (*C var*), 729
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.isThereExtraRxBytes (*C var*), 730
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.lastTimeDataBytes (*C var*), 730
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.lastTimeTCD (*C var*), 730
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.lpspiSoftwareTCD (*C var*), 731
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.nbytes (*C var*), 731
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.readRegRemainingTimes (*C var*), 730
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.rxBuffIfNull (*C var*), 731
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.rxData (*C var*), 730
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.rxRemainingByteCount (*C var*), 730
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.rxWatermark (*C var*), 729
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.state (*C var*), 731
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.totalByteCount (*C var*), 730
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.transferConfigRx (*C var*), 730
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.transferConfigTx (*C var*), 731
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.transmitCommand (*C var*), 731
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.txBuffIfNull (*C var*), 731
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.txData (*C var*), 730
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.txRemainingByteCount (*C var*), 730
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.userData (*C var*), 731
drivers_MCX_MCXA_MCXA366._lpspi_master_edma_handle.writeRegRemainingTimes (*C var*), 730
drivers_MCX_MCXA_MCXA366._lpspi_master_handle (*C struct*), 722
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.bytesEachRead (*C var*), 723

drivers_MCX_MCXA_MCXA366._lpspi_master_handle.bytesEachWrite (*C var*), 723
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.bytesPerFrame (*C var*), 723
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.callback (*C var*), 724
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.fifoSize (*C var*), 723
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.frameSize (*C var*), 723
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.isByteSwap (*C var*), 723
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.isPcsContinuous (*C var*), 723
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.isTxMask (*C var*), 723
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.readRegRemainingTimes (*C var*), 723
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.rxData (*C var*), 723
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.rxRemainingByteCount (*C var*), 723
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.rxWatermark (*C var*), 723
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.state (*C var*), 724
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.totalByteCount (*C var*), 723
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.txBuffIfNull (*C var*), 724
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.txData (*C var*), 723
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.txRemainingByteCount (*C var*), 723
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.userData (*C var*), 724
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.writeRegRemainingTimes (*C var*), 723
drivers_MCX_MCXA_MCXA366._lpspi_master_handle.writeTcrInIsr (*C var*), 723
drivers_MCX_MCXA_MCXA366._lpspi_master_slave_mode (*C enum*), 713
drivers_MCX_MCXA_MCXA366._lpspi_master_slave_mode.kLPSPI_Master (*C enumerator*), 713
drivers_MCX_MCXA_MCXA366._lpspi_master_slave_mode.kLPSPI_Slave (*C enumerator*), 713
drivers_MCX_MCXA_MCXA366._lpspi_match_config (*C enum*), 715
drivers_MCX_MCXA_MCXA366._lpspi_match_config.kLPSPI_1stWordAndM1EqualsM0andM1 (*C enumerator*), 716
drivers_MCX_MCXA_MCXA366._lpspi_match_config.kLPSPI_1stWordEqualsM0and2ndWordEqualsM1 (*C enumerator*), 716
drivers_MCX_MCXA_MCXA366._lpspi_match_config.kLPSPI_1stWordEqualsM0orM1 (*C enumerator*), 715
drivers_MCX_MCXA_MCXA366._lpspi_match_config.kLPSPI_AnyWordAndM1EqualsM0andM1 (*C enumerator*), 716
drivers_MCX_MCXA_MCXA366._lpspi_match_config.kLPSPI_AnyWordEqualsM0andNxtWordEqualsM1 (*C enumerator*), 716
drivers_MCX_MCXA_MCXA366._lpspi_match_config.kLPSPI_AnyWordEqualsM0orM1 (*C enumerator*), 715
drivers_MCX_MCXA_MCXA366._lpspi_match_config.kLPSPI_MatchDisabled (*C enumerator*), 715
drivers_MCX_MCXA_MCXA366._lpspi_pcs_polarity (*C enum*), 714
drivers_MCX_MCXA_MCXA366._lpspi_pcs_polarity_config (*C enum*), 714
drivers_MCX_MCXA_MCXA366._lpspi_pcs_polarity_config.kLPSPI_PcsActiveHigh (*C enumerator*), 714
drivers_MCX_MCXA_MCXA366._lpspi_pcs_polarity_config.kLPSPI_PcsActiveLow (*C enumerator*), 714
drivers_MCX_MCXA_MCXA366._lpspi_pcs_polarity.kLPSPI_Pcs0ActiveLow (*C enumerator*), 714
drivers_MCX_MCXA_MCXA366._lpspi_pcs_polarity.kLPSPI_Pcs1ActiveLow (*C enumerator*), 714
drivers_MCX_MCXA_MCXA366._lpspi_pcs_polarity.kLPSPI_Pcs2ActiveLow (*C enumerator*), 714
drivers_MCX_MCXA_MCXA366._lpspi_pcs_polarity.kLPSPI_Pcs3ActiveLow (*C enumerator*), 714
drivers_MCX_MCXA_MCXA366._lpspi_pcs_polarity.kLPSPI_PcsAllActiveLow (*C enumerator*), 714
drivers_MCX_MCXA_MCXA366._lpspi_pin_config (*C enum*), 716
drivers_MCX_MCXA_MCXA366._lpspi_pin_config.kLPSPI_SdiInSdiOut (*C enumerator*), 716
drivers_MCX_MCXA_MCXA366._lpspi_pin_config.kLPSPI_SdiInSdoOut (*C enumerator*), 716
drivers_MCX_MCXA_MCXA366._lpspi_pin_config.kLPSPI_SdoInSdiOut (*C enumerator*), 716
drivers_MCX_MCXA_MCXA366._lpspi_pin_config.kLPSPI_SdoInSdoOut (*C enumerator*), 716
drivers_MCX_MCXA_MCXA366._lpspi_shift_direction (*C enum*), 715
drivers_MCX_MCXA_MCXA366._lpspi_shift_direction.kLPSPI_LsbFirst (*C enumerator*), 715
drivers_MCX_MCXA_MCXA366._lpspi_shift_direction.kLPSPI_MsbFirst (*C enumerator*), 715
drivers_MCX_MCXA_MCXA366._lpspi_slave_config (*C struct*), 721

drivers_MCX_MCXA_MCXA366._lpspi_slave_config.bitsPerFrame (*C var*), 721
drivers_MCX_MCXA_MCXA366._lpspi_slave_config.cpha (*C var*), 722
drivers_MCX_MCXA_MCXA366._lpspi_slave_config.cpol (*C var*), 722
drivers_MCX_MCXA_MCXA366._lpspi_slave_config.dataOutConfig (*C var*), 722
drivers_MCX_MCXA_MCXA366._lpspi_slave_config.direction (*C var*), 722
drivers_MCX_MCXA_MCXA366._lpspi_slave_config.pcsActiveHighOrLow (*C var*), 722
drivers_MCX_MCXA_MCXA366._lpspi_slave_config.pinCfg (*C var*), 722
drivers_MCX_MCXA_MCXA366._lpspi_slave_config.whichPcs (*C var*), 722
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle (*C struct*), 731
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.bytesEachRead (*C var*), 732
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.bytesEachWrite (*C var*), 732
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.bytesLastRead (*C var*), 732
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.callback (*C var*), 733
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.edmaRxRegToRxDataHandle (*C var*), 733
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.edmaTxDataToTxRegHandle (*C var*), 733
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.errorCount (*C var*), 732
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.fifoSize (*C var*), 731
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.isByteSwap (*C var*), 731
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.isThereExtraRxBytes (*C var*), 732
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.lpspiSoftwareTCD (*C var*), 733
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.nbytes (*C var*), 732
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.readRegRemainingTimes (*C var*), 732
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.rxBuffIfNull (*C var*), 732
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.rxData (*C var*), 732
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.rxRemainingByteCount (*C var*), 732
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.rxWatermark (*C var*), 731
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.state (*C var*), 732
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.totalByteCount (*C var*), 732
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.txBuffIfNull (*C var*), 732
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.txData (*C var*), 732
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.txRemainingByteCount (*C var*), 732
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.userData (*C var*), 733
drivers_MCX_MCXA_MCXA366._lpspi_slave_edma_handle.writeRegRemainingTimes (*C var*), 732
drivers_MCX_MCXA_MCXA366._lpspi_slave_handle (*C struct*), 724
drivers_MCX_MCXA_MCXA366._lpspi_slave_handle.bytesEachRead (*C var*), 724
drivers_MCX_MCXA_MCXA366._lpspi_slave_handle.bytesEachWrite (*C var*), 724
drivers_MCX_MCXA_MCXA366._lpspi_slave_handle.callback (*C var*), 725
drivers_MCX_MCXA_MCXA366._lpspi_slave_handle.errorCount (*C var*), 725
drivers_MCX_MCXA_MCXA366._lpspi_slave_handle.fifoSize (*C var*), 724
drivers_MCX_MCXA_MCXA366._lpspi_slave_handle.isByteSwap (*C var*), 724
drivers_MCX_MCXA_MCXA366._lpspi_slave_handle.readRegRemainingTimes (*C var*), 725
drivers_MCX_MCXA_MCXA366._lpspi_slave_handle.rxData (*C var*), 724
drivers_MCX_MCXA_MCXA366._lpspi_slave_handle.rxRemainingByteCount (*C var*), 724
drivers_MCX_MCXA_MCXA366._lpspi_slave_handle.rxWatermark (*C var*), 724
drivers_MCX_MCXA_MCXA366._lpspi_slave_handle.state (*C var*), 725
drivers_MCX_MCXA_MCXA366._lpspi_slave_handle.totalByteCount (*C var*), 725
drivers_MCX_MCXA_MCXA366._lpspi_slave_handle.txData (*C var*), 724
drivers_MCX_MCXA_MCXA366._lpspi_slave_handle.txRemainingByteCount (*C var*), 724
drivers_MCX_MCXA_MCXA366._lpspi_slave_handle.userData (*C var*), 725
drivers_MCX_MCXA_MCXA366._lpspi_slave_handle.writeRegRemainingTimes (*C var*), 724
drivers_MCX_MCXA_MCXA366._lpspi_transfer (*C struct*), 722
drivers_MCX_MCXA_MCXA366._lpspi_transfer_config_flag_for_master (*C enum*), 717
drivers_MCX_MCXA_MCXA366._lpspi_transfer_config_flag_for_master.kLPSPI_MasterByteSwap (*C enumerator*), 717
drivers_MCX_MCXA_MCXA366._lpspi_transfer_config_flag_for_master.kLPSPI_MasterPcs0 (*C enumerator*), 717

drivers_MCX_MCXA_MCXA366._lpspi_transfer_config_flag_for_master.kLPSPI_MasterPcs1 (*C enumerator*), 717
drivers_MCX_MCXA_MCXA366._lpspi_transfer_config_flag_for_master.kLPSPI_MasterPcs2 (*C enumerator*), 717
drivers_MCX_MCXA_MCXA366._lpspi_transfer_config_flag_for_master.kLPSPI_MasterPcs3 (*C enumerator*), 717
drivers_MCX_MCXA_MCXA366._lpspi_transfer_config_flag_for_master.kLPSPI_MasterPcsContinuous (*C enumerator*), 717
drivers_MCX_MCXA_MCXA366._lpspi_transfer_config_flag_for_slave (*C enum*), 718
drivers_MCX_MCXA_MCXA366._lpspi_transfer_config_flag_for_slave.kLPSPI_SlaveByteSwap (*C enumerator*), 718
drivers_MCX_MCXA_MCXA366._lpspi_transfer_config_flag_for_slave.kLPSPI_SlavePcs0 (*C enumerator*), 718
drivers_MCX_MCXA_MCXA366._lpspi_transfer_config_flag_for_slave.kLPSPI_SlavePcs1 (*C enumerator*), 718
drivers_MCX_MCXA_MCXA366._lpspi_transfer_config_flag_for_slave.kLPSPI_SlavePcs2 (*C enumerator*), 718
drivers_MCX_MCXA_MCXA366._lpspi_transfer_config_flag_for_slave.kLPSPI_SlavePcs3 (*C enumerator*), 718
drivers_MCX_MCXA_MCXA366._lpspi_transfer_state (*C enum*), 718
drivers_MCX_MCXA_MCXA366._lpspi_transfer_state.kLPSPI_Busy (*C enumerator*), 718
drivers_MCX_MCXA_MCXA366._lpspi_transfer_state.kLPSPI_Error (*C enumerator*), 718
drivers_MCX_MCXA_MCXA366._lpspi_transfer_state.kLPSPI_Idle (*C enumerator*), 718
drivers_MCX_MCXA_MCXA366._lpspi_transfer_width (*C enum*), 716
drivers_MCX_MCXA_MCXA366._lpspi_transfer_width.kLPSPI_FourBitXfer (*C enumerator*), 717
drivers_MCX_MCXA_MCXA366._lpspi_transfer_width.kLPSPI_SingleBitXfer (*C enumerator*), 716
drivers_MCX_MCXA_MCXA366._lpspi_transfer_width.kLPSPI_TwoBitXfer (*C enumerator*), 716
drivers_MCX_MCXA_MCXA366._lpspi_transfer.configFlags (*C var*), 722
drivers_MCX_MCXA_MCXA366._lpspi_transfer.dataSize (*C var*), 722
drivers_MCX_MCXA_MCXA366._lpspi_transfer.rxData (*C var*), 722
drivers_MCX_MCXA_MCXA366._lpspi_transfer.txData (*C var*), 722
drivers_MCX_MCXA_MCXA366._lpspi_which_pcs_config (*C enum*), 713
drivers_MCX_MCXA_MCXA366._lpspi_which_pcs_config.kLPSPI_Pcs0 (*C enumerator*), 714
drivers_MCX_MCXA_MCXA366._lpspi_which_pcs_config.kLPSPI_Pcs1 (*C enumerator*), 714
drivers_MCX_MCXA_MCXA366._lpspi_which_pcs_config.kLPSPI_Pcs2 (*C enumerator*), 714
drivers_MCX_MCXA_MCXA366._lpspi_which_pcs_config.kLPSPI_Pcs3 (*C enumerator*), 714
drivers_MCX_MCXA_MCXA366._lptmr_config (*C struct*), 738
drivers_MCX_MCXA_MCXA366._lptmr_config.bypassPrescaler (*C var*), 739
drivers_MCX_MCXA_MCXA366._lptmr_config.enableFreeRunning (*C var*), 739
drivers_MCX_MCXA_MCXA366._lptmr_config.pinPolarity (*C var*), 739
drivers_MCX_MCXA_MCXA366._lptmr_config.pinSelect (*C var*), 739
drivers_MCX_MCXA_MCXA366._lptmr_config.prescalerClockSource (*C var*), 739
drivers_MCX_MCXA_MCXA366._lptmr_config.timerMode (*C var*), 739
drivers_MCX_MCXA_MCXA366._lptmr_config.value (*C var*), 739
drivers_MCX_MCXA_MCXA366._lptmr_interrupt_enable (*C enum*), 737
drivers_MCX_MCXA_MCXA366._lptmr_interrupt_enable.kLPTMR_TimerInterruptEnable (*C enumerator*), 737
drivers_MCX_MCXA_MCXA366._lptmr_pin_polarity (*C enum*), 735
drivers_MCX_MCXA_MCXA366._lptmr_pin_polarity.kLPTMR_PinPolarityActiveHigh (*C enumerator*), 736
drivers_MCX_MCXA_MCXA366._lptmr_pin_polarity.kLPTMR_PinPolarityActiveLow (*C enumerator*), 736
drivers_MCX_MCXA_MCXA366._lptmr_pin_select (*C enum*), 735
drivers_MCX_MCXA_MCXA366._lptmr_pin_select.kLPTMR_PinSelectInput_0 (*C enumerator*), 735
drivers_MCX_MCXA_MCXA366._lptmr_pin_select.kLPTMR_PinSelectInput_1 (*C enumerator*), 735

drivers_MCX_MCXA_MCXA366._lptmr_pin_select.kLPTMR_PinSelectInput_2 (*C enumerator*), 735
drivers_MCX_MCXA_MCXA366._lptmr_pin_select.kLPTMR_PinSelectInput_3 (*C enumerator*), 735
drivers_MCX_MCXA_MCXA366._lptmr_prescaler_clock_select (*C enum*), 737
drivers_MCX_MCXA_MCXA366._lptmr_prescaler_glitch_value (*C enum*), 736
drivers_MCX_MCXA_MCXA366._lptmr_prescaler_glitch_value.kLPTMR_Prescale_Glitch_0 (*C enumerator*), 736
drivers_MCX_MCXA_MCXA366._lptmr_prescaler_glitch_value.kLPTMR_Prescale_Glitch_1 (*C enumerator*), 736
drivers_MCX_MCXA_MCXA366._lptmr_prescaler_glitch_value.kLPTMR_Prescale_Glitch_2 (*C enumerator*), 736
drivers_MCX_MCXA_MCXA366._lptmr_prescaler_glitch_value.kLPTMR_Prescale_Glitch_3 (*C enumerator*), 736
drivers_MCX_MCXA_MCXA366._lptmr_prescaler_glitch_value.kLPTMR_Prescale_Glitch_4 (*C enumerator*), 736
drivers_MCX_MCXA_MCXA366._lptmr_prescaler_glitch_value.kLPTMR_Prescale_Glitch_5 (*C enumerator*), 736
drivers_MCX_MCXA_MCXA366._lptmr_prescaler_glitch_value.kLPTMR_Prescale_Glitch_6 (*C enumerator*), 736
drivers_MCX_MCXA_MCXA366._lptmr_prescaler_glitch_value.kLPTMR_Prescale_Glitch_7 (*C enumerator*), 736
drivers_MCX_MCXA_MCXA366._lptmr_prescaler_glitch_value.kLPTMR_Prescale_Glitch_8 (*C enumerator*), 736
drivers_MCX_MCXA_MCXA366._lptmr_prescaler_glitch_value.kLPTMR_Prescale_Glitch_9 (*C enumerator*), 737
drivers_MCX_MCXA_MCXA366._lptmr_prescaler_glitch_value.kLPTMR_Prescale_Glitch_10 (*C enumerator*), 737
drivers_MCX_MCXA_MCXA366._lptmr_prescaler_glitch_value.kLPTMR_Prescale_Glitch_11 (*C enumerator*), 737
drivers_MCX_MCXA_MCXA366._lptmr_prescaler_glitch_value.kLPTMR_Prescale_Glitch_12 (*C enumerator*), 737
drivers_MCX_MCXA_MCXA366._lptmr_prescaler_glitch_value.kLPTMR_Prescale_Glitch_13 (*C enumerator*), 737
drivers_MCX_MCXA_MCXA366._lptmr_prescaler_glitch_value.kLPTMR_Prescale_Glitch_14 (*C enumerator*), 737
drivers_MCX_MCXA_MCXA366._lptmr_prescaler_glitch_value.kLPTMR_Prescale_Glitch_15 (*C enumerator*), 737
drivers_MCX_MCXA_MCXA366._lptmr_status_flags (*C enum*), 737
drivers_MCX_MCXA_MCXA366._lptmr_status_flags.kLPTMR_TimerCompareFlag (*C enumerator*), 737
drivers_MCX_MCXA_MCXA366._lptmr_timer_mode (*C enum*), 736
drivers_MCX_MCXA_MCXA366._lptmr_timer_mode.kLPTMR_TimerModePulseCounter (*C enumerator*), 736
drivers_MCX_MCXA_MCXA366._lptmr_timer_mode.kLPTMR_TimerModeTimeCounter (*C enumerator*), 736
drivers_MCX_MCXA_MCXA366._lpuart_config (*C struct*), 757
drivers_MCX_MCXA_MCXA366._lpuart_config.baudRate_Bps (*C var*), 757
drivers_MCX_MCXA_MCXA366._lpuart_config.dataBitsCount (*C var*), 757
drivers_MCX_MCXA_MCXA366._lpuart_config.enableRx (*C var*), 758
drivers_MCX_MCXA_MCXA366._lpuart_config.enableRxRTS (*C var*), 757
drivers_MCX_MCXA_MCXA366._lpuart_config.enableTx (*C var*), 758
drivers_MCX_MCXA_MCXA366._lpuart_config.enableTxCTS (*C var*), 757
drivers_MCX_MCXA_MCXA366._lpuart_config.enableTxRTS (*C var*), 757
drivers_MCX_MCXA_MCXA366._lpuart_config.inverseTxd (*C var*), 758
drivers_MCX_MCXA_MCXA366._lpuart_config.isMsb (*C var*), 757
drivers_MCX_MCXA_MCXA366._lpuart_config.parityMode (*C var*), 757
drivers_MCX_MCXA_MCXA366._lpuart_config.rtsWatermark (*C var*), 758

drivers_MCX_MCXA_MCXA366._lpuart_config.rxFifoWatermark (*C var*), 757
drivers_MCX_MCXA_MCXA366._lpuart_config.rxIdleConfig (*C var*), 758
drivers_MCX_MCXA_MCXA366._lpuart_config.rxIdleType (*C var*), 758
drivers_MCX_MCXA_MCXA366._lpuart_config.stopBitCount (*C var*), 757
drivers_MCX_MCXA_MCXA366._lpuart_config.swapTxdRxd (*C var*), 758
drivers_MCX_MCXA_MCXA366._lpuart_config.txCtsConfig (*C var*), 758
drivers_MCX_MCXA_MCXA366._lpuart_config.txCtsSource (*C var*), 757
drivers_MCX_MCXA_MCXA366._lpuart_config.txFifoWatermark (*C var*), 757
drivers_MCX_MCXA_MCXA366._lpuart_config.txRtsPolarity (*C var*), 758
drivers_MCX_MCXA_MCXA366._lpuart_data_bits (*C enum*), 752
drivers_MCX_MCXA_MCXA366._lpuart_data_bits.kLPUART_EightDataBits (*C enumerator*), 752
drivers_MCX_MCXA_MCXA366._lpuart_data_bits.kLPUART_SevenDataBits (*C enumerator*), 752
drivers_MCX_MCXA_MCXA366._lpuart_edma_handle (*C struct*), 763
drivers_MCX_MCXA_MCXA366._lpuart_edma_handle.callback (*C var*), 763
drivers_MCX_MCXA_MCXA366._lpuart_edma_handle.nbytes (*C var*), 763
drivers_MCX_MCXA_MCXA366._lpuart_edma_handle.rxDataSizeAll (*C var*), 763
drivers_MCX_MCXA_MCXA366._lpuart_edma_handle.rxEdmaHandle (*C var*), 763
drivers_MCX_MCXA_MCXA366._lpuart_edma_handle.rxState (*C var*), 763
drivers_MCX_MCXA_MCXA366._lpuart_edma_handle.txDataSizeAll (*C var*), 763
drivers_MCX_MCXA_MCXA366._lpuart_edma_handle.txEdmaHandle (*C var*), 763
drivers_MCX_MCXA_MCXA366._lpuart_edma_handle.txState (*C var*), 763
drivers_MCX_MCXA_MCXA366._lpuart_edma_handle.userData (*C var*), 763
drivers_MCX_MCXA_MCXA366._lpuart_flags (*C enum*), 754
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_AllClearFlags (*C enumerator*), 756
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_AllFlags (*C enumerator*), 756
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_DataMatch1Flag (*C enumerator*), 755
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_DataMatch2Flag (*C enumerator*), 755
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_FramingErrorFlag (*C enumerator*), 755
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_IdleLineFlag (*C enumerator*), 755
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_LinBreakFlag (*C enumerator*), 755
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_NoiseErrorFlag (*C enumerator*), 755
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_ParityErrorFlag (*C enumerator*), 755
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_RxActiveEdgeFlag (*C enumerator*), 755
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_RxActiveFlag (*C enumerator*), 755
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_RxDataRegFullFlag (*C enumerator*), 755
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_RxFifoEmptyFlag (*C enumerator*), 755
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_RxFifoUnderflowFlag (*C enumerator*), 756
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_RxOverrunFlag (*C enumerator*), 755
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_TransmissionCompleteFlag (*C enumerator*), 755
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_TxDataRegEmptyFlag (*C enumerator*), 755
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_TxFifoEmptyFlag (*C enumerator*), 755
drivers_MCX_MCXA_MCXA366._lpuart_flags.kLPUART_TxFifoOverflowFlag (*C enumerator*), 756
drivers_MCX_MCXA_MCXA366._lpuart_handle (*C struct*), 758
drivers_MCX_MCXA_MCXA366._lpuart_handle.___unnamed69___ (*C union*), 760
drivers_MCX_MCXA_MCXA366._lpuart_handle.___unnamed69___.txData (*C var*), 760
drivers_MCX_MCXA_MCXA366._lpuart_handle.___unnamed69___.txData16 (*C var*), 760
drivers_MCX_MCXA_MCXA366._lpuart_handle.___unnamed71___ (*C union*), 760
drivers_MCX_MCXA_MCXA366._lpuart_handle.___unnamed71___.rxData (*C var*), 760
drivers_MCX_MCXA_MCXA366._lpuart_handle.___unnamed71___.rxData16 (*C var*), 760
drivers_MCX_MCXA_MCXA366._lpuart_handle.___unnamed73___ (*C union*), 760
drivers_MCX_MCXA_MCXA366._lpuart_handle.___unnamed73___.rxRingBuffer (*C var*), 760

drivers_MCX_MCXA_MCXA366._lpuart_handle.___unnamed73___.rxRingBuffer16 (*C var*), 760
drivers_MCX_MCXA_MCXA366._lpuart_handle.callback (*C var*), 759
drivers_MCX_MCXA_MCXA366._lpuart_handle.is16bitData (*C var*), 759
drivers_MCX_MCXA_MCXA366._lpuart_handle.isSevenDataBits (*C var*), 759
drivers_MCX_MCXA_MCXA366._lpuart_handle.rxDataSize (*C var*), 759
drivers_MCX_MCXA_MCXA366._lpuart_handle.rxDataSizeAll (*C var*), 759
drivers_MCX_MCXA_MCXA366._lpuart_handle.rxRingBufferHead (*C var*), 759
drivers_MCX_MCXA_MCXA366._lpuart_handle.rxRingBufferSize (*C var*), 759
drivers_MCX_MCXA_MCXA366._lpuart_handle.rxRingBufferTail (*C var*), 759
drivers_MCX_MCXA_MCXA366._lpuart_handle.rxState (*C var*), 759
drivers_MCX_MCXA_MCXA366._lpuart_handle.txDataSize (*C var*), 758
drivers_MCX_MCXA_MCXA366._lpuart_handle.txDataSizeAll (*C var*), 758
drivers_MCX_MCXA_MCXA366._lpuart_handle.txState (*C var*), 759
drivers_MCX_MCXA_MCXA366._lpuart_handle.userData (*C var*), 759
drivers_MCX_MCXA_MCXA366._lpuart_idle_config (*C enum*), 753
drivers_MCX_MCXA_MCXA366._lpuart_idle_config.kLPUART_IdleCharacter1 (*C enumerator*), 753
drivers_MCX_MCXA_MCXA366._lpuart_idle_config.kLPUART_IdleCharacter2 (*C enumerator*), 753
drivers_MCX_MCXA_MCXA366._lpuart_idle_config.kLPUART_IdleCharacter4 (*C enumerator*), 753
drivers_MCX_MCXA_MCXA366._lpuart_idle_config.kLPUART_IdleCharacter8 (*C enumerator*), 753
drivers_MCX_MCXA_MCXA366._lpuart_idle_config.kLPUART_IdleCharacter16 (*C enumerator*), 753
drivers_MCX_MCXA_MCXA366._lpuart_idle_config.kLPUART_IdleCharacter32 (*C enumerator*), 753
drivers_MCX_MCXA_MCXA366._lpuart_idle_config.kLPUART_IdleCharacter64 (*C enumerator*), 753
drivers_MCX_MCXA_MCXA366._lpuart_idle_config.kLPUART_IdleCharacter128 (*C enumerator*), 753
drivers_MCX_MCXA_MCXA366._lpuart_idle_type_select (*C enum*), 753
drivers_MCX_MCXA_MCXA366._lpuart_idle_type_select.kLPUART_IdleTypeStartBit (*C enumerator*), 753
drivers_MCX_MCXA_MCXA366._lpuart_idle_type_select.kLPUART_IdleTypeStopBit (*C enumerator*), 753
drivers_MCX_MCXA_MCXA366._lpuart_interrupt_enable (*C enum*), 753
drivers_MCX_MCXA_MCXA366._lpuart_interrupt_enable.kLPUART_AllInterruptEnable (*C enumerator*), 754
drivers_MCX_MCXA_MCXA366._lpuart_interrupt_enable.kLPUART_FramingErrorInterruptEnable (*C enumerator*), 754
drivers_MCX_MCXA_MCXA366._lpuart_interrupt_enable.kLPUART_IdleLineInterruptEnable (*C enumerator*), 754
drivers_MCX_MCXA_MCXA366._lpuart_interrupt_enable.kLPUART_LinBreakInterruptEnable (*C enumerator*), 754
drivers_MCX_MCXA_MCXA366._lpuart_interrupt_enable.kLPUART_Match1InterruptEnable (*C enumerator*), 754
drivers_MCX_MCXA_MCXA366._lpuart_interrupt_enable.kLPUART_Match2InterruptEnable (*C enumerator*), 754
drivers_MCX_MCXA_MCXA366._lpuart_interrupt_enable.kLPUART_NoiseErrorInterruptEnable (*C enumerator*), 754
drivers_MCX_MCXA_MCXA366._lpuart_interrupt_enable.kLPUART_ParityErrorInterruptEnable (*C enumerator*), 754
drivers_MCX_MCXA_MCXA366._lpuart_interrupt_enable.kLPUART_RxActiveEdgeInterruptEnable (*C enumerator*), 754
drivers_MCX_MCXA_MCXA366._lpuart_interrupt_enable.kLPUART_RxDataRegFullInterruptEnable (*C enumerator*), 754
drivers_MCX_MCXA_MCXA366._lpuart_interrupt_enable.kLPUART_RxFifoUnderflowInterruptEnable

(*C enumerator*), 754
drivers_MCX_MCXA_MCXA366._lpuart_interrupt_enable.kLPUART_RxOverrunInterruptEnable (*C enumerator*), 754
drivers_MCX_MCXA_MCXA366._lpuart_interrupt_enable.kLPUART_TransmissionCompleteInterruptEnable (*C enumerator*), 754
drivers_MCX_MCXA_MCXA366._lpuart_interrupt_enable.kLPUART_TxDataRegEmptyInterruptEnable (*C enumerator*), 754
drivers_MCX_MCXA_MCXA366._lpuart_interrupt_enable.kLPUART_TxFifoOverflowInterruptEnable (*C enumerator*), 754
drivers_MCX_MCXA_MCXA366._lpuart_parity_mode (*C enum*), 751
drivers_MCX_MCXA_MCXA366._lpuart_parity_mode.kLPUART_ParityDisabled (*C enumerator*), 751
drivers_MCX_MCXA_MCXA366._lpuart_parity_mode.kLPUART_ParityEven (*C enumerator*), 751
drivers_MCX_MCXA_MCXA366._lpuart_parity_mode.kLPUART_ParityOdd (*C enumerator*), 752
drivers_MCX_MCXA_MCXA366._lpuart_stop_bit_count (*C enum*), 752
drivers_MCX_MCXA_MCXA366._lpuart_stop_bit_count.kLPUART_OneStopBit (*C enumerator*), 752
drivers_MCX_MCXA_MCXA366._lpuart_stop_bit_count.kLPUART_TwoStopBit (*C enumerator*), 752
drivers_MCX_MCXA_MCXA366._lpuart_transfer (*C struct*), 758
drivers_MCX_MCXA_MCXA366._lpuart_transfer.___unnamed67___ (*C union*), 759
drivers_MCX_MCXA_MCXA366._lpuart_transfer.___unnamed67___.data (*C var*), 759
drivers_MCX_MCXA_MCXA366._lpuart_transfer.___unnamed67___.rxData (*C var*), 759
drivers_MCX_MCXA_MCXA366._lpuart_transfer.___unnamed67___.rxData16 (*C var*), 759
drivers_MCX_MCXA_MCXA366._lpuart_transfer.___unnamed67___.txData (*C var*), 759
drivers_MCX_MCXA_MCXA366._lpuart_transfer.___unnamed67___.txData16 (*C var*), 760
drivers_MCX_MCXA_MCXA366._lpuart_transfer.dataSize (*C var*), 758
drivers_MCX_MCXA_MCXA366._lpuart_transmit_cts_config (*C enum*), 752
drivers_MCX_MCXA_MCXA366._lpuart_transmit_cts_config.kLPUART_CtsSampleAtIdle (*C enumerator*), 752
drivers_MCX_MCXA_MCXA366._lpuart_transmit_cts_config.kLPUART_CtsSampleAtStart (*C enumerator*), 752
drivers_MCX_MCXA_MCXA366._lpuart_transmit_cts_source (*C enum*), 752
drivers_MCX_MCXA_MCXA366._lpuart_transmit_cts_source.kLPUART_CtsSourceMatchResult (*C enumerator*), 752
drivers_MCX_MCXA_MCXA366._lpuart_transmit_cts_source.kLPUART_CtsSourcePin (*C enumerator*), 752
drivers_MCX_MCXA_MCXA366._lpuart_transmit_rts_polarity (*C enum*), 752
drivers_MCX_MCXA_MCXA366._lpuart_transmit_rts_polarity.kLPUART_RtsPolarityHigh (*C enumerator*), 753
drivers_MCX_MCXA_MCXA366._lpuart_transmit_rts_polarity.kLPUART_RtsPolarityLow (*C enumerator*), 753
drivers_MCX_MCXA_MCXA366._mau_config (*C struct*), 768
drivers_MCX_MCXA_MCXA366._mau_config.enableRes0Interrupt (*C var*), 768
drivers_MCX_MCXA_MCXA366._mau_config.enableRes1Interrupt (*C var*), 768
drivers_MCX_MCXA_MCXA366._mau_config.enableRes2Interrupt (*C var*), 768
drivers_MCX_MCXA_MCXA366._mau_config.enableRes3Interrupt (*C var*), 768
drivers_MCX_MCXA_MCXA366._mau_data_type (*C enum*), 766
drivers_MCX_MCXA_MCXA366._mau_data_type.kMAU_DT_FLOAT (*C enumerator*), 766
drivers_MCX_MCXA_MCXA366._mau_data_type.kMAU_DT_INT (*C enumerator*), 766
drivers_MCX_MCXA_MCXA366._mau_data_type.kMAU_DT_Q1X (*C enumerator*), 766
drivers_MCX_MCXA_MCXA366._mau_data_type.kMAU_DT_UINT (*C enumerator*), 766
drivers_MCX_MCXA_MCXA366._mau_flags (*C enum*), 767
drivers_MCX_MCXA_MCXA366._mau_flags.kMAU_FLAG_DZ (*C enumerator*), 767
drivers_MCX_MCXA_MCXA366._mau_flags.kMAU_FLAG_ERR (*C enumerator*), 767
drivers_MCX_MCXA_MCXA366._mau_flags.kMAU_FLAG_FULL (*C enumerator*), 767
drivers_MCX_MCXA_MCXA366._mau_flags.kMAU_FLAG_NV (*C enumerator*), 767

drivers_MCX_MCXA_MCXA366._mau_flags.kMAU_FLAG_NX (*C enumerator*), 767
drivers_MCX_MCXA_MCXA366._mau_flags.kMAU_FLAG_OF (*C enumerator*), 767
drivers_MCX_MCXA_MCXA366._mau_flags.kMAU_FLAG_OVWR (*C enumerator*), 767
drivers_MCX_MCXA_MCXA366._mau_flags.kMAU_FLAG_UF (*C enumerator*), 767
drivers_MCX_MCXA_MCXA366._mau_mopc (*C enum*), 767
drivers_MCX_MCXA_MCXA366._mau_mopc.kMAU_MOPC_ATAN (*C enumerator*), 767
drivers_MCX_MCXA_MCXA366._mau_mopc.kMAU_MOPC_BYPASS (*C enumerator*), 767
drivers_MCX_MCXA_MCXA366._mau_mopc.kMAU_MOPC_COS (*C enumerator*), 767
drivers_MCX_MCXA_MCXA366._mau_mopc.kMAU_MOPC_RECIP (*C enumerator*), 767
drivers_MCX_MCXA_MCXA366._mau_mopc.kMAU_MOPC_SIN (*C enumerator*), 767
drivers_MCX_MCXA_MCXA366._mau_mopc.kMAU_MOPC_SQRT (*C enumerator*), 767
drivers_MCX_MCXA_MCXA366._mau_mopc.kMAU_MOPC_SQRT_RECIP (*C enumerator*), 767
drivers_MCX_MCXA_MCXA366._mau_result (*C enum*), 766
drivers_MCX_MCXA_MCXA366._mau_result.kMAU_RES0 (*C enumerator*), 766
drivers_MCX_MCXA_MCXA366._mau_result.kMAU_RES1 (*C enumerator*), 766
drivers_MCX_MCXA_MCXA366._mau_result.kMAU_RES2 (*C enumerator*), 766
drivers_MCX_MCXA_MCXA366._mau_result.kMAU_RES3 (*C enumerator*), 766
drivers_MCX_MCXA_MCXA366._opamp_bias_current (*C enum*), 847
drivers_MCX_MCXA_MCXA366._opamp_bias_current.kOPAMP_ChangeToDouble (*C enumerator*), 847
drivers_MCX_MCXA_MCXA366._opamp_bias_current.kOPAMP_ChangeToHalf (*C enumerator*), 847
drivers_MCX_MCXA_MCXA366._opamp_bias_current.kOPAMP_ChangeToQuarter (*C enumerator*), 847
drivers_MCX_MCXA_MCXA366._opamp_bias_current.kOPAMP_NoChange (*C enumerator*), 847
drivers_MCX_MCXA_MCXA366._opamp_comp_cap (*C enum*), 847
drivers_MCX_MCXA_MCXA366._opamp_comp_cap.kOPAMP_FitGain2x (*C enumerator*), 847
drivers_MCX_MCXA_MCXA366._opamp_comp_cap.kOPAMP_FitGain4x (*C enumerator*), 847
drivers_MCX_MCXA_MCXA366._opamp_comp_cap.kOPAMP_FitGain8x (*C enumerator*), 847
drivers_MCX_MCXA_MCXA366._opamp_comp_cap.kOPAMP_FitGain16x (*C enumerator*), 847
drivers_MCX_MCXA_MCXA366._opamp_config (*C struct*), 848
drivers_MCX_MCXA_MCXA366._opamp_config.biasCurrent (*C var*), 848
drivers_MCX_MCXA_MCXA366._opamp_config.compCap (*C var*), 848
drivers_MCX_MCXA_MCXA366._opamp_config.enable (*C var*), 848
drivers_MCX_MCXA_MCXA366._ostimer_flags (*C enum*), 853
drivers_MCX_MCXA_MCXA366._ostimer_flags.kOSTIMER_MatchInterruptFlag (*C enumerator*), 853
drivers_MCX_MCXA_MCXA366._port_digital_filter_clock_source (*C enum*), 860
drivers_MCX_MCXA_MCXA366._port_digital_filter_clock_source.kPORT_BusClock (*C enumerator*), 860
drivers_MCX_MCXA_MCXA366._port_digital_filter_clock_source.kPORT_LpoClock (*C enumerator*), 860
drivers_MCX_MCXA_MCXA366._port_digital_filter_config (*C struct*), 860
drivers_MCX_MCXA_MCXA366._port_digital_filter_config.clockSource (*C var*), 861
drivers_MCX_MCXA_MCXA366._port_digital_filter_config.digitalFilterWidth (*C var*), 861
drivers_MCX_MCXA_MCXA366._port_drive_strength (*C enum*), 857
drivers_MCX_MCXA_MCXA366._port_drive_strength1 (*C enum*), 857
drivers_MCX_MCXA_MCXA366._port_drive_strength1.kPORT_DoubleDriveStrength (*C enumerator*), 858
drivers_MCX_MCXA_MCXA366._port_drive_strength1.kPORT_NormalDriveStrength (*C enumerator*), 858
drivers_MCX_MCXA_MCXA366._port_drive_strength.kPORT_HighDriveStrength (*C enumerator*), 857
drivers_MCX_MCXA_MCXA366._port_drive_strength.kPORT_LowDriveStrength (*C enumerator*), 857
drivers_MCX_MCXA_MCXA366._port_input_buffer (*C enum*), 858
drivers_MCX_MCXA_MCXA366._port_input_buffer.kPORT_InputBufferDisable (*C enumerator*), 858

drivers_MCX_MCXA_MCXA366._port_input_buffer.kPORT_InputBufferEnable (*C enumerator*), 858
drivers_MCX_MCXA_MCXA366._port_invet_input (*C enum*), 858
drivers_MCX_MCXA_MCXA366._port_invet_input.kPORT_InputInvert (*C enumerator*), 858
drivers_MCX_MCXA_MCXA366._port_invet_input.kPORT_InputNormal (*C enumerator*), 858
drivers_MCX_MCXA_MCXA366._port_lock_register (*C enum*), 858
drivers_MCX_MCXA_MCXA366._port_lock_register.kPORT_LockRegister (*C enumerator*), 858
drivers_MCX_MCXA_MCXA366._port_lock_register.kPORT_UnlockRegister (*C enumerator*), 858
drivers_MCX_MCXA_MCXA366._port_mux (*C enum*), 858
drivers_MCX_MCXA_MCXA366._port_mux.kPORT_MuxAlt0 (*C enumerator*), 859
drivers_MCX_MCXA_MCXA366._port_mux.kPORT_MuxAlt1 (*C enumerator*), 859
drivers_MCX_MCXA_MCXA366._port_mux.kPORT_MuxAlt2 (*C enumerator*), 859
drivers_MCX_MCXA_MCXA366._port_mux.kPORT_MuxAlt3 (*C enumerator*), 859
drivers_MCX_MCXA_MCXA366._port_mux.kPORT_MuxAlt4 (*C enumerator*), 859
drivers_MCX_MCXA_MCXA366._port_mux.kPORT_MuxAlt5 (*C enumerator*), 859
drivers_MCX_MCXA_MCXA366._port_mux.kPORT_MuxAlt6 (*C enumerator*), 859
drivers_MCX_MCXA_MCXA366._port_mux.kPORT_MuxAlt7 (*C enumerator*), 859
drivers_MCX_MCXA_MCXA366._port_mux.kPORT_MuxAlt8 (*C enumerator*), 859
drivers_MCX_MCXA_MCXA366._port_mux.kPORT_MuxAlt9 (*C enumerator*), 859
drivers_MCX_MCXA_MCXA366._port_mux.kPORT_MuxAlt10 (*C enumerator*), 859
drivers_MCX_MCXA_MCXA366._port_mux.kPORT_MuxAlt11 (*C enumerator*), 859
drivers_MCX_MCXA_MCXA366._port_mux.kPORT_MuxAlt12 (*C enumerator*), 859
drivers_MCX_MCXA_MCXA366._port_mux.kPORT_MuxAlt13 (*C enumerator*), 859
drivers_MCX_MCXA_MCXA366._port_mux.kPORT_MuxAlt14 (*C enumerator*), 859
drivers_MCX_MCXA_MCXA366._port_mux.kPORT_MuxAlt15 (*C enumerator*), 859
drivers_MCX_MCXA_MCXA366._port_mux.kPORT_MuxAsGpio (*C enumerator*), 858
drivers_MCX_MCXA_MCXA366._port_mux.kPORT_PinDisabledOrAnalog (*C enumerator*), 858
drivers_MCX_MCXA_MCXA366._port_open_drain_enable (*C enum*), 857
drivers_MCX_MCXA_MCXA366._port_open_drain_enable.kPORT_OpenDrainDisable (*C enumerator*), 857
drivers_MCX_MCXA_MCXA366._port_open_drain_enable.kPORT_OpenDrainEnable (*C enumerator*), 857
drivers_MCX_MCXA_MCXA366._port_passive_filter_enable (*C enum*), 857
drivers_MCX_MCXA_MCXA366._port_passive_filter_enable.kPORT_PassiveFilterDisable (*C enumerator*), 857
drivers_MCX_MCXA_MCXA366._port_passive_filter_enable.kPORT_PassiveFilterEnable (*C enumerator*), 857
drivers_MCX_MCXA_MCXA366._port_pin_config (*C struct*), 861
drivers_MCX_MCXA_MCXA366._port_pin_config.driveStrength (*C var*), 861
drivers_MCX_MCXA_MCXA366._port_pin_config.driveStrength1 (*C var*), 861
drivers_MCX_MCXA_MCXA366._port_pin_config.inputBuffer (*C var*), 861
drivers_MCX_MCXA_MCXA366._port_pin_config.invertInput (*C var*), 861
drivers_MCX_MCXA_MCXA366._port_pin_config.lockRegister (*C var*), 861
drivers_MCX_MCXA_MCXA366._port_pin_config.openDrainEnable (*C var*), 861
drivers_MCX_MCXA_MCXA366._port_pin_config.passiveFilterEnable (*C var*), 861
drivers_MCX_MCXA_MCXA366._port_pin_config.pullSelect (*C var*), 861
drivers_MCX_MCXA_MCXA366._port_pin_config.pullValueSelect (*C var*), 861
drivers_MCX_MCXA_MCXA366._port_pin_config.slewRate (*C var*), 861
drivers_MCX_MCXA_MCXA366._port_pull (*C enum*), 856
drivers_MCX_MCXA_MCXA366._port_pull_value (*C enum*), 856
drivers_MCX_MCXA_MCXA366._port_pull_value.kPORT_HighPullResistor (*C enumerator*), 857
drivers_MCX_MCXA_MCXA366._port_pull_value.kPORT_LowPullResistor (*C enumerator*), 856
drivers_MCX_MCXA_MCXA366._port_pull.kPORT_PullDisable (*C enumerator*), 856
drivers_MCX_MCXA_MCXA366._port_pull.kPORT_PullDown (*C enumerator*), 856
drivers_MCX_MCXA_MCXA366._port_pull.kPORT_PullUp (*C enumerator*), 856
drivers_MCX_MCXA_MCXA366._port_slew_rate (*C enum*), 857
drivers_MCX_MCXA_MCXA366._port_slew_rate.kPORT_FastSlewRate (*C enumerator*), 857
drivers_MCX_MCXA_MCXA366._port_slew_rate.kPORT_SlowSlewRate (*C enumerator*), 857

drivers_MCX_MCXA_MCXA366._port_version_info (*C struct*), 861
drivers_MCX_MCXA_MCXA366._port_version_info.feature (*C var*), 862
drivers_MCX_MCXA_MCXA366._port_version_info.major (*C var*), 862
drivers_MCX_MCXA_MCXA366._port_version_info.minor (*C var*), 862
drivers_MCX_MCXA_MCXA366._port_voltage_range (*C enum*), 860
drivers_MCX_MCXA_MCXA366._port_voltage_range.kPORT_VoltageRange1Dot71V_3Dot6V (*C enumerator*), 860
drivers_MCX_MCXA_MCXA366._port_voltage_range.kPORT_VoltageRange2Dot70V_3Dot6V (*C enumerator*), 860
drivers_MCX_MCXA_MCXA366._pwm_channels (*C enum*), 867
drivers_MCX_MCXA_MCXA366._pwm_channels.kPWM_PwmA (*C enumerator*), 867
drivers_MCX_MCXA_MCXA366._pwm_channels.kPWM_PwmB (*C enumerator*), 867
drivers_MCX_MCXA_MCXA366._pwm_channels.kPWM_PwmX (*C enumerator*), 867
drivers_MCX_MCXA_MCXA366._pwm_chnl_pair_operation (*C enum*), 873
drivers_MCX_MCXA_MCXA366._pwm_chnl_pair_operation.kPWM_ComplementaryPwmA (*C enumerator*), 873
drivers_MCX_MCXA_MCXA366._pwm_chnl_pair_operation.kPWM_ComplementaryPwmB (*C enumerator*), 873
drivers_MCX_MCXA_MCXA366._pwm_chnl_pair_operation.kPWM_Independent (*C enumerator*), 873
drivers_MCX_MCXA_MCXA366._pwm_clock_prescale (*C enum*), 869
drivers_MCX_MCXA_MCXA366._pwm_clock_prescale.kPWM_Prescale_Divide_1 (*C enumerator*), 869
drivers_MCX_MCXA_MCXA366._pwm_clock_prescale.kPWM_Prescale_Divide_2 (*C enumerator*), 869
drivers_MCX_MCXA_MCXA366._pwm_clock_prescale.kPWM_Prescale_Divide_4 (*C enumerator*), 869
drivers_MCX_MCXA_MCXA366._pwm_clock_prescale.kPWM_Prescale_Divide_8 (*C enumerator*), 869
drivers_MCX_MCXA_MCXA366._pwm_clock_prescale.kPWM_Prescale_Divide_16 (*C enumerator*), 869
drivers_MCX_MCXA_MCXA366._pwm_clock_prescale.kPWM_Prescale_Divide_32 (*C enumerator*), 869
drivers_MCX_MCXA_MCXA366._pwm_clock_prescale.kPWM_Prescale_Divide_64 (*C enumerator*), 869
drivers_MCX_MCXA_MCXA366._pwm_clock_prescale.kPWM_Prescale_Divide_128 (*C enumerator*), 869
drivers_MCX_MCXA_MCXA366._pwm_clock_source (*C enum*), 868
drivers_MCX_MCXA_MCXA366._pwm_clock_source.kPWM_BusClock (*C enumerator*), 868
drivers_MCX_MCXA_MCXA366._pwm_clock_source.kPWM_ExternalClock (*C enumerator*), 869
drivers_MCX_MCXA_MCXA366._pwm_clock_source.kPWM_Submodule0Clock (*C enumerator*), 869
drivers_MCX_MCXA_MCXA366._pwm_config (*C struct*), 889
drivers_MCX_MCXA_MCXA366._pwm_config.clockSource (*C var*), 889
drivers_MCX_MCXA_MCXA366._pwm_config.enableDebugMode (*C var*), 889
drivers_MCX_MCXA_MCXA366._pwm_config.forceTrigger (*C var*), 890
drivers_MCX_MCXA_MCXA366._pwm_config.initializationControl (*C var*), 889
drivers_MCX_MCXA_MCXA366._pwm_config.pairOperation (*C var*), 889
drivers_MCX_MCXA_MCXA366._pwm_config.prescale (*C var*), 889
drivers_MCX_MCXA_MCXA366._pwm_config.reloadFrequency (*C var*), 890
drivers_MCX_MCXA_MCXA366._pwm_config.reloadLogic (*C var*), 890
drivers_MCX_MCXA_MCXA366._pwm_config.reloadSelect (*C var*), 890
drivers_MCX_MCXA_MCXA366._pwm_dma_enable (*C enum*), 877
drivers_MCX_MCXA_MCXA366._pwm_dma_enable.kPWM_CaptureA0DMAEnable (*C enumerator*), 877
drivers_MCX_MCXA_MCXA366._pwm_dma_enable.kPWM_CaptureA1DMAEnable (*C enumerator*), 877

drivers_MCX_MCXA_MCXA366._pwm_dma_enable.kPWM_CaptureB0DMAEnable (*C enumerator*), 877
drivers_MCX_MCXA_MCXA366._pwm_dma_enable.kPWM_CaptureB1DMAEnable (*C enumerator*), 877
drivers_MCX_MCXA_MCXA366._pwm_dma_enable.kPWM_CaptureX0DMAEnable (*C enumerator*), 877
drivers_MCX_MCXA_MCXA366._pwm_dma_enable.kPWM_CaptureX1DMAEnable (*C enumerator*), 877
drivers_MCX_MCXA_MCXA366._pwm_dma_source_select (*C enum*), 877
drivers_MCX_MCXA_MCXA366._pwm_dma_source_select.kPWM_DMALocalReload (*C enumerator*), 877
drivers_MCX_MCXA_MCXA366._pwm_dma_source_select.kPWM_DMALocalSync (*C enumerator*), 877
drivers_MCX_MCXA_MCXA366._pwm_dma_source_select.kPWM_DMARequestDisable (*C enumerator*), 877
drivers_MCX_MCXA_MCXA366._pwm_dma_source_select.kPWM_DMAWatermarksEnable (*C enumerator*), 877
drivers_MCX_MCXA_MCXA366._pwm_fault_channels (*C enum*), 872
drivers_MCX_MCXA_MCXA366._pwm_fault_channels.kPWM_faultchannel_0 (*C enumerator*), 872
drivers_MCX_MCXA_MCXA366._pwm_fault_clear (*C enum*), 879
drivers_MCX_MCXA_MCXA366._pwm_fault_clear.kPWM_Automatic (*C enumerator*), 879
drivers_MCX_MCXA_MCXA366._pwm_fault_clear.kPWM_ManualNormal (*C enumerator*), 879
drivers_MCX_MCXA_MCXA366._pwm_fault_clear.kPWM_ManualSafety (*C enumerator*), 879
drivers_MCX_MCXA_MCXA366._pwm_fault_disable (*C enum*), 872
drivers_MCX_MCXA_MCXA366._pwm_fault_disable.kPWM_FaultDisable_0 (*C enumerator*), 872
drivers_MCX_MCXA_MCXA366._pwm_fault_disable.kPWM_FaultDisable_1 (*C enumerator*), 872
drivers_MCX_MCXA_MCXA366._pwm_fault_disable.kPWM_FaultDisable_2 (*C enumerator*), 872
drivers_MCX_MCXA_MCXA366._pwm_fault_disable.kPWM_FaultDisable_3 (*C enumerator*), 872
drivers_MCX_MCXA_MCXA366._pwm_fault_input (*C enum*), 872
drivers_MCX_MCXA_MCXA366._pwm_fault_input_filter_param (*C struct*), 890
drivers_MCX_MCXA_MCXA366._pwm_fault_input_filter_param.faultFilterCount (*C var*), 890
drivers_MCX_MCXA_MCXA366._pwm_fault_input_filter_param.faultFilterPeriod (*C var*), 890
drivers_MCX_MCXA_MCXA366._pwm_fault_input_filter_param.faultGlitchStretch (*C var*), 890
drivers_MCX_MCXA_MCXA366._pwm_fault_input.kPWM_Fault_0 (*C enumerator*), 872
drivers_MCX_MCXA_MCXA366._pwm_fault_input.kPWM_Fault_1 (*C enumerator*), 872
drivers_MCX_MCXA_MCXA366._pwm_fault_input.kPWM_Fault_2 (*C enumerator*), 872
drivers_MCX_MCXA_MCXA366._pwm_fault_input.kPWM_Fault_3 (*C enumerator*), 872
drivers_MCX_MCXA_MCXA366._pwm_fault_param (*C struct*), 890
drivers_MCX_MCXA_MCXA366._pwm_fault_param.enableCombinationalPath (*C var*), 890
drivers_MCX_MCXA_MCXA366._pwm_fault_param.faultClearingMode (*C var*), 890
drivers_MCX_MCXA_MCXA366._pwm_fault_param.faultLevel (*C var*), 890
drivers_MCX_MCXA_MCXA366._pwm_fault_param.recoverMode (*C var*), 890
drivers_MCX_MCXA_MCXA366._pwm_fault_recovery_mode (*C enum*), 874
drivers_MCX_MCXA_MCXA366._pwm_fault_recovery_mode.kPWM_NoRecovery (*C enumerator*), 874
drivers_MCX_MCXA_MCXA366._pwm_fault_recovery_mode.kPWM_RecoverFullCycle (*C enumerator*), 874
drivers_MCX_MCXA_MCXA366._pwm_fault_recovery_mode.kPWM_RecoverHalfAndFullCycle (*C enumerator*), 874
drivers_MCX_MCXA_MCXA366._pwm_fault_recovery_mode.kPWM_RecoverHalfCycle (*C enumerator*), 874
drivers_MCX_MCXA_MCXA366._pwm_fault_state (*C enum*), 878
drivers_MCX_MCXA_MCXA366._pwm_fault_state.kPWM_PwmFaultState0 (*C enumerator*), 878
drivers_MCX_MCXA_MCXA366._pwm_fault_state.kPWM_PwmFaultState1 (*C enumerator*), 878
drivers_MCX_MCXA_MCXA366._pwm_fault_state.kPWM_PwmFaultState2 (*C enumerator*), 878
drivers_MCX_MCXA_MCXA366._pwm_fault_state.kPWM_PwmFaultState3 (*C enumerator*), 878
drivers_MCX_MCXA_MCXA366._pwm_force_output_trigger (*C enum*), 869

drivers_MCX_MCXA_MCXA366._pwm_force_output_trigger.kPWM_Force_External (*C enumerator*), 870
drivers_MCX_MCXA_MCXA366._pwm_force_output_trigger.kPWM_Force_ExternalSync (*C enumerator*), 870
drivers_MCX_MCXA_MCXA366._pwm_force_output_trigger.kPWM_Force_Local (*C enumerator*), 869
drivers_MCX_MCXA_MCXA366._pwm_force_output_trigger.kPWM_Force_LocalReload (*C enumerator*), 869
drivers_MCX_MCXA_MCXA366._pwm_force_output_trigger.kPWM_Force_LocalSync (*C enumerator*), 870
drivers_MCX_MCXA_MCXA366._pwm_force_output_trigger.kPWM_Force_Master (*C enumerator*), 869
drivers_MCX_MCXA_MCXA366._pwm_force_output_trigger.kPWM_Force_MasterReload (*C enumerator*), 870
drivers_MCX_MCXA_MCXA366._pwm_force_output_trigger.kPWM_Force_MasterSync (*C enumerator*), 870
drivers_MCX_MCXA_MCXA366._pwm_force_signal (*C enum*), 873
drivers_MCX_MCXA_MCXA366._pwm_force_signal.kPWM_InvertedPwm (*C enumerator*), 873
drivers_MCX_MCXA_MCXA366._pwm_force_signal.kPWM_SoftwareControl (*C enumerator*), 873
drivers_MCX_MCXA_MCXA366._pwm_force_signal.kPWM_UseExternal (*C enumerator*), 873
drivers_MCX_MCXA_MCXA366._pwm_force_signal.kPWM_UsePwm (*C enumerator*), 873
drivers_MCX_MCXA_MCXA366._pwm_init_source (*C enum*), 870
drivers_MCX_MCXA_MCXA366._pwm_init_source.kPWM_Initialize_ExtSync (*C enumerator*), 871
drivers_MCX_MCXA_MCXA366._pwm_init_source.kPWM_Initialize_LocalSync (*C enumerator*), 870
drivers_MCX_MCXA_MCXA366._pwm_init_source.kPWM_Initialize_MasterReload (*C enumerator*), 870
drivers_MCX_MCXA_MCXA366._pwm_init_source.kPWM_Initialize_MasterSync (*C enumerator*), 870
drivers_MCX_MCXA_MCXA366._pwm_input_capture_edge (*C enum*), 872
drivers_MCX_MCXA_MCXA366._pwm_input_capture_edge.kPWM_Disable (*C enumerator*), 873
drivers_MCX_MCXA_MCXA366._pwm_input_capture_edge.kPWM_FallingEdge (*C enumerator*), 873
drivers_MCX_MCXA_MCXA366._pwm_input_capture_edge.kPWM_RiseAndFallEdge (*C enumerator*), 873
drivers_MCX_MCXA_MCXA366._pwm_input_capture_edge.kPWM_RisingEdge (*C enumerator*), 873
drivers_MCX_MCXA_MCXA366._pwm_input_capture_param (*C struct*), 890
drivers_MCX_MCXA_MCXA366._pwm_input_capture_param.captureInputSel (*C var*), 891
drivers_MCX_MCXA_MCXA366._pwm_input_capture_param.edge0 (*C var*), 891
drivers_MCX_MCXA_MCXA366._pwm_input_capture_param.edge1 (*C var*), 891
drivers_MCX_MCXA_MCXA366._pwm_input_capture_param.edgeCompareValue (*C var*), 891
drivers_MCX_MCXA_MCXA366._pwm_input_capture_param.enableOneShotCapture (*C var*), 891
drivers_MCX_MCXA_MCXA366._pwm_input_capture_param.fifoWatermark (*C var*), 891
drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable (*C enum*), 874
drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable.kPWM_CaptureA0InterruptEnable (*C enumerator*), 875
drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable.kPWM_CaptureA1InterruptEnable (*C enumerator*), 875
drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable.kPWM_CaptureB0InterruptEnable (*C enumerator*), 875
drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable.kPWM_CaptureB1InterruptEnable (*C enumerator*), 875
drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable.kPWM_CaptureX0InterruptEnable (*C enumerator*), 875
drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable.kPWM_CaptureX1InterruptEnable (*C enumerator*), 875

drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable.kPWM_CompareVal0InterruptEnable (*C enumerator*), 874
drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable.kPWM_CompareVal1InterruptEnable (*C enumerator*), 874
drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable.kPWM_CompareVal2InterruptEnable (*C enumerator*), 874
drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable.kPWM_CompareVal3InterruptEnable (*C enumerator*), 874
drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable.kPWM_CompareVal4InterruptEnable (*C enumerator*), 874
drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable.kPWM_CompareVal5InterruptEnable (*C enumerator*), 874
drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable.kPWM_Fault0InterruptEnable (*C enumerator*), 875
drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable.kPWM_Fault1InterruptEnable (*C enumerator*), 875
drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable.kPWM_Fault2InterruptEnable (*C enumerator*), 875
drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable.kPWM_Fault3InterruptEnable (*C enumerator*), 875
drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable.kPWM_ReloadErrorInterruptEnable (*C enumerator*), 875
drivers_MCX_MCXA_MCXA366._pwm_interrupt_enable.kPWM_ReloadInterruptEnable (*C enumerator*), 875
drivers_MCX_MCXA_MCXA366._pwm_level_select (*C enum*), 878
drivers_MCX_MCXA_MCXA366._pwm_level_select.kPWM_HighTrue (*C enumerator*), 878
drivers_MCX_MCXA_MCXA366._pwm_level_select.kPWM_LowTrue (*C enumerator*), 878
drivers_MCX_MCXA_MCXA366._pwm_load_frequency (*C enum*), 871
drivers_MCX_MCXA_MCXA366._pwm_load_frequency.kPWM_LoadEvery2Oportunity (*C enumerator*), 871
drivers_MCX_MCXA_MCXA366._pwm_load_frequency.kPWM_LoadEvery3Oportunity (*C enumerator*), 871
drivers_MCX_MCXA_MCXA366._pwm_load_frequency.kPWM_LoadEvery4Oportunity (*C enumerator*), 871
drivers_MCX_MCXA_MCXA366._pwm_load_frequency.kPWM_LoadEvery5Oportunity (*C enumerator*), 871
drivers_MCX_MCXA_MCXA366._pwm_load_frequency.kPWM_LoadEvery6Oportunity (*C enumerator*), 871
drivers_MCX_MCXA_MCXA366._pwm_load_frequency.kPWM_LoadEvery7Oportunity (*C enumerator*), 871
drivers_MCX_MCXA_MCXA366._pwm_load_frequency.kPWM_LoadEvery8Oportunity (*C enumerator*), 871
drivers_MCX_MCXA_MCXA366._pwm_load_frequency.kPWM_LoadEvery9Oportunity (*C enumerator*), 871
drivers_MCX_MCXA_MCXA366._pwm_load_frequency.kPWM_LoadEvery10Oportunity (*C enumerator*), 871
drivers_MCX_MCXA_MCXA366._pwm_load_frequency.kPWM_LoadEvery11Oportunity (*C enumerator*), 871
drivers_MCX_MCXA_MCXA366._pwm_load_frequency.kPWM_LoadEvery12Oportunity (*C enumerator*), 871
drivers_MCX_MCXA_MCXA366._pwm_load_frequency.kPWM_LoadEvery13Oportunity (*C enumerator*), 871
drivers_MCX_MCXA_MCXA366._pwm_load_frequency.kPWM_LoadEvery14Oportunity (*C enumerator*), 871
drivers_MCX_MCXA_MCXA366._pwm_load_frequency.kPWM_LoadEvery15Oportunity (*C enumerator*), 872
drivers_MCX_MCXA_MCXA366._pwm_load_frequency.kPWM_LoadEvery16Oportunity (*C enumerator*), 872

drivers_MCX_MCXA_MCXA366._pwm_load_frequency.kPWM_LoadEveryOportunity (*C enumerator*), 871
drivers_MCX_MCXA_MCXA366._pwm_mode (*C enum*), 878
drivers_MCX_MCXA_MCXA366._pwm_mode.kPWM_CenterAligned (*C enumerator*), 878
drivers_MCX_MCXA_MCXA366._pwm_mode.kPWM_EdgeAligned (*C enumerator*), 878
drivers_MCX_MCXA_MCXA366._pwm_mode.kPWM_SignedCenterAligned (*C enumerator*), 878
drivers_MCX_MCXA_MCXA366._pwm_mode.kPWM_SignedEdgeAligned (*C enumerator*), 878
drivers_MCX_MCXA_MCXA366._pwm_module_control (*C enum*), 879
drivers_MCX_MCXA_MCXA366._pwm_module_control.kPWM_Control_Module_0 (*C enumerator*), 879
drivers_MCX_MCXA_MCXA366._pwm_module_control.kPWM_Control_Module_1 (*C enumerator*), 879
drivers_MCX_MCXA_MCXA366._pwm_module_control.kPWM_Control_Module_2 (*C enumerator*), 879
drivers_MCX_MCXA_MCXA366._pwm_module_control.kPWM_Control_Module_3 (*C enumerator*), 879
drivers_MCX_MCXA_MCXA366._pwm_output_state (*C enum*), 870
drivers_MCX_MCXA_MCXA366._pwm_output_state.kPWM_HighState (*C enumerator*), 870
drivers_MCX_MCXA_MCXA366._pwm_output_state.kPWM_InvertState (*C enumerator*), 870
drivers_MCX_MCXA_MCXA366._pwm_output_state.kPWM_LowState (*C enumerator*), 870
drivers_MCX_MCXA_MCXA366._pwm_output_state.kPWM_MaskState (*C enumerator*), 870
drivers_MCX_MCXA_MCXA366._pwm_output_state.kPWM_NormalState (*C enumerator*), 870
drivers_MCX_MCXA_MCXA366._pwm_register_reload (*C enum*), 873
drivers_MCX_MCXA_MCXA366._pwm_register_reload.kPWM_ReloadImmediate (*C enumerator*), 873
drivers_MCX_MCXA_MCXA366._pwm_register_reload.kPWM_ReloadPwmFullCycle (*C enumerator*), 874
drivers_MCX_MCXA_MCXA366._pwm_register_reload.kPWM_ReloadPwmHalfAndFullCycle (*C enumerator*), 874
drivers_MCX_MCXA_MCXA366._pwm_register_reload.kPWM_ReloadPwmHalfCycle (*C enumerator*), 874
drivers_MCX_MCXA_MCXA366._pwm_reload_source_select (*C enum*), 878
drivers_MCX_MCXA_MCXA366._pwm_reload_source_select.kPWM_LocalReload (*C enumerator*), 878
drivers_MCX_MCXA_MCXA366._pwm_reload_source_select.kPWM_MasterReload (*C enumerator*), 879
drivers_MCX_MCXA_MCXA366._pwm_signal_param (*C struct*), 889
drivers_MCX_MCXA_MCXA366._pwm_signal_param.deadtimeValue (*C var*), 889
drivers_MCX_MCXA_MCXA366._pwm_signal_param.dutyCyclePercent (*C var*), 889
drivers_MCX_MCXA_MCXA366._pwm_signal_param.faultState (*C var*), 889
drivers_MCX_MCXA_MCXA366._pwm_signal_param.level (*C var*), 889
drivers_MCX_MCXA_MCXA366._pwm_signal_param.pwmChannel (*C var*), 889
drivers_MCX_MCXA_MCXA366._pwm_signal_param.pwmchannelenable (*C var*), 889
drivers_MCX_MCXA_MCXA366._pwm_status_flags (*C enum*), 875
drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_CaptureA0Flag (*C enumerator*), 876
drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_CaptureA1Flag (*C enumerator*), 876
drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_CaptureB0Flag (*C enumerator*), 876
drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_CaptureB1Flag (*C enumerator*), 876
drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_CaptureX0Flag (*C enumerator*), 876
drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_CaptureX1Flag (*C enumerator*), 876
drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_CompareVal0Flag (*C enumerator*), 875
drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_CompareVal1Flag (*C enumerator*), 875
drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_CompareVal2Flag (*C enumerator*), 875
drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_CompareVal3Flag (*C enumerator*), 876

drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_CompareVal4Flag (*C enumerator*), 876
drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_CompareVal5Flag (*C enumerator*), 876
drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_Fault0Flag (*C enumerator*), 876
drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_Fault1Flag (*C enumerator*), 876
drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_Fault2Flag (*C enumerator*), 876
drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_Fault3Flag (*C enumerator*), 876
drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_RegUpdatedFlag (*C enumerator*), 876
drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_ReloadErrorFlag (*C enumerator*), 876
drivers_MCX_MCXA_MCXA366._pwm_status_flags.kPWM_ReloadFlag (*C enumerator*), 876
drivers_MCX_MCXA_MCXA366._pwm_submodule (*C enum*), 867
drivers_MCX_MCXA_MCXA366._pwm_submodule.kPWM_Module_0 (*C enumerator*), 867
drivers_MCX_MCXA_MCXA366._pwm_submodule.kPWM_Module_1 (*C enumerator*), 867
drivers_MCX_MCXA_MCXA366._pwm_submodule.kPWM_Module_2 (*C enumerator*), 867
drivers_MCX_MCXA_MCXA366._pwm_value_register (*C enum*), 867
drivers_MCX_MCXA_MCXA366._pwm_value_register_mask (*C enum*), 868
drivers_MCX_MCXA_MCXA366._pwm_value_register_mask.kPWM_ValueRegisterMask_0 (*C enumerator*), 868
drivers_MCX_MCXA_MCXA366._pwm_value_register_mask.kPWM_ValueRegisterMask_1 (*C enumerator*), 868
drivers_MCX_MCXA_MCXA366._pwm_value_register_mask.kPWM_ValueRegisterMask_2 (*C enumerator*), 868
drivers_MCX_MCXA_MCXA366._pwm_value_register_mask.kPWM_ValueRegisterMask_3 (*C enumerator*), 868
drivers_MCX_MCXA_MCXA366._pwm_value_register_mask.kPWM_ValueRegisterMask_4 (*C enumerator*), 868
drivers_MCX_MCXA_MCXA366._pwm_value_register_mask.kPWM_ValueRegisterMask_5 (*C enumerator*), 868
drivers_MCX_MCXA_MCXA366._pwm_value_register.kPWM_ValueRegister_0 (*C enumerator*), 868
drivers_MCX_MCXA_MCXA366._pwm_value_register.kPWM_ValueRegister_1 (*C enumerator*), 868
drivers_MCX_MCXA_MCXA366._pwm_value_register.kPWM_ValueRegister_2 (*C enumerator*), 868
drivers_MCX_MCXA_MCXA366._pwm_value_register.kPWM_ValueRegister_3 (*C enumerator*), 868
drivers_MCX_MCXA_MCXA366._pwm_value_register.kPWM_ValueRegister_4 (*C enumerator*), 868
drivers_MCX_MCXA_MCXA366._pwm_value_register.kPWM_ValueRegister_5 (*C enumerator*), 868
drivers_MCX_MCXA_MCXA366._pwm_watermark_control (*C enum*), 877
drivers_MCX_MCXA_MCXA366._pwm_watermark_control.kPWM_FIFOWatermarksAND (*C enumerator*), 877
drivers_MCX_MCXA_MCXA366._pwm_watermark_control.kPWM_FIFOWatermarksOR (*C enumerator*), 877
drivers_MCX_MCXA_MCXA366._rtc_config (*C struct*), 899
drivers_MCX_MCXA_MCXA366._rtc_config.clockOutput (*C var*), 899
drivers_MCX_MCXA_MCXA366._rtc_config.compensationInterval (*C var*), 899
drivers_MCX_MCXA_MCXA366._rtc_config.compensationTime (*C var*), 899
drivers_MCX_MCXA_MCXA366._rtc_config.supervisorAccess (*C var*), 899
drivers_MCX_MCXA_MCXA366._rtc_config.updateMode (*C var*), 899
drivers_MCX_MCXA_MCXA366._rtc_config.wakeupSelect (*C var*), 899
drivers_MCX_MCXA_MCXA366._rtc_datetime (*C struct*), 898
drivers_MCX_MCXA_MCXA366._rtc_datetime.day (*C var*), 898
drivers_MCX_MCXA_MCXA366._rtc_datetime.hour (*C var*), 898

drivers_MCX_MCXA_MCXA366._rtc_datetime.minute (*C var*), 898
drivers_MCX_MCXA_MCXA366._rtc_datetime.month (*C var*), 898
drivers_MCX_MCXA_MCXA366._rtc_datetime.second (*C var*), 898
drivers_MCX_MCXA_MCXA366._rtc_datetime.year (*C var*), 898
drivers_MCX_MCXA_MCXA366._rtc_interrupt_enable (*C enum*), 894
drivers_MCX_MCXA_MCXA366._rtc_interrupt_enable.kRTC_AlarmInterruptEnable (*C enumerator*), 895
drivers_MCX_MCXA_MCXA366._rtc_interrupt_enable.kRTC_FlashSecurityInterruptEnable (*C enumerator*), 895
drivers_MCX_MCXA_MCXA366._rtc_interrupt_enable.kRTC_LossOfClockInterruptEnable (*C enumerator*), 895
drivers_MCX_MCXA_MCXA366._rtc_interrupt_enable.kRTC_MonotonicOverflowInterruptEnable (*C enumerator*), 895
drivers_MCX_MCXA_MCXA366._rtc_interrupt_enable.kRTC_SecondsInterruptEnable (*C enumerator*), 895
drivers_MCX_MCXA_MCXA366._rtc_interrupt_enable.kRTC_SecurityModuleInterruptEnable (*C enumerator*), 895
drivers_MCX_MCXA_MCXA366._rtc_interrupt_enable.kRTC_TamperPinInterruptEnable (*C enumerator*), 895
drivers_MCX_MCXA_MCXA366._rtc_interrupt_enable.kRTC_TestModeInterruptEnable (*C enumerator*), 895
drivers_MCX_MCXA_MCXA366._rtc_interrupt_enable.kRTC_TimeInvalidInterruptEnable (*C enumerator*), 894
drivers_MCX_MCXA_MCXA366._rtc_interrupt_enable.kRTC_TimeOverflowInterruptEnable (*C enumerator*), 894
drivers_MCX_MCXA_MCXA366._rtc_osc_cap_load (*C enum*), 896
drivers_MCX_MCXA_MCXA366._rtc_osc_cap_load.kRTC_Capacitor_2p (*C enumerator*), 896
drivers_MCX_MCXA_MCXA366._rtc_osc_cap_load.kRTC_Capacitor_4p (*C enumerator*), 896
drivers_MCX_MCXA_MCXA366._rtc_osc_cap_load.kRTC_Capacitor_8p (*C enumerator*), 896
drivers_MCX_MCXA_MCXA366._rtc_osc_cap_load.kRTC_Capacitor_16p (*C enumerator*), 896
drivers_MCX_MCXA_MCXA366._rtc_pin_config (*C struct*), 898
drivers_MCX_MCXA_MCXA366._rtc_pin_config.filterEnable (*C var*), 899
drivers_MCX_MCXA_MCXA366._rtc_pin_config.inputLogic (*C var*), 899
drivers_MCX_MCXA_MCXA366._rtc_pin_config.pinActiveLow (*C var*), 899
drivers_MCX_MCXA_MCXA366._rtc_pin_config.pullEnable (*C var*), 899
drivers_MCX_MCXA_MCXA366._rtc_pin_config.pullSelectNegate (*C var*), 899
drivers_MCX_MCXA_MCXA366._rtc_status_flags (*C enum*), 895
drivers_MCX_MCXA_MCXA366._rtc_status_flags.kRTC_AlarmFlag (*C enumerator*), 895
drivers_MCX_MCXA_MCXA366._rtc_status_flags.kRTC_FlashSecurityFlag (*C enumerator*), 895
drivers_MCX_MCXA_MCXA366._rtc_status_flags.kRTC_LossOfClockTamperFlag (*C enumerator*), 896
drivers_MCX_MCXA_MCXA366._rtc_status_flags.kRTC_MonotonicOverflowFlag (*C enumerator*), 895
drivers_MCX_MCXA_MCXA366._rtc_status_flags.kRTC_SecurityTamperFlag (*C enumerator*), 895
drivers_MCX_MCXA_MCXA366._rtc_status_flags.kRTC_TamperInterruptDetectFlag (*C enumerator*), 895
drivers_MCX_MCXA_MCXA366._rtc_status_flags.kRTC_TamperPinFlag (*C enumerator*), 895
drivers_MCX_MCXA_MCXA366._rtc_status_flags.kRTC_TestModeFlag (*C enumerator*), 895
drivers_MCX_MCXA_MCXA366._rtc_status_flags.kRTC_TimeInvalidFlag (*C enumerator*), 895
drivers_MCX_MCXA_MCXA366._rtc_status_flags.kRTC_TimeOverflowFlag (*C enumerator*), 895
drivers_MCX_MCXA_MCXA366._rtc_timer_seconds_interrupt_frequency (*C enum*), 896
drivers_MCX_MCXA_MCXA366._rtc_timer_seconds_interrupt_frequency.kRTC_TimerSecondsFrequency1Hz (*C enumerator*), 896
drivers_MCX_MCXA_MCXA366._rtc_timer_seconds_interrupt_frequency.kRTC_TimerSecondsFrequency2Hz (*C enumerator*), 896
drivers_MCX_MCXA_MCXA366._rtc_timer_seconds_interrupt_frequency.kRTC_TimerSecondsFrequency4Hz (*C enumerator*), 896

drivers_MCX_MCXA_MCXA366._rtc_timer_seconds_interrupt_frequency.kRTC_TimerSecondsFrequency8Hz (*C enumerator*), 896
drivers_MCX_MCXA_MCXA366._rtc_timer_seconds_interrupt_frequency.kRTC_TimerSecondsFrequency16Hz (*C enumerator*), 896
drivers_MCX_MCXA_MCXA366._rtc_timer_seconds_interrupt_frequency.kRTC_TimerSecondsFrequency32Hz (*C enumerator*), 896
drivers_MCX_MCXA_MCXA366._rtc_timer_seconds_interrupt_frequency.kRTC_TimerSecondsFrequency64Hz (*C enumerator*), 896
drivers_MCX_MCXA_MCXA366._rtc_timer_seconds_interrupt_frequency.kRTC_TimerSecondsFrequency128Hz (*C enumerator*), 896
drivers_MCX_MCXA_MCXA366._SDK_AtomicLocalCompareAndSet (*C function*), 630
drivers_MCX_MCXA_MCXA366._SDK_AtomicTestAndSet (*C function*), 630
drivers_MCX_MCXA_MCXA366._slcd_blink_mode (*C enum*), 907
drivers_MCX_MCXA_MCXA366._slcd_blink_mode.kSLCD_AltDisplayBlink (*C enumerator*), 907
drivers_MCX_MCXA_MCXA366._slcd_blink_mode.kSLCD_BlankDisplayBlink (*C enumerator*), 907
drivers_MCX_MCXA_MCXA366._slcd_blink_rate (*C enum*), 905
drivers_MCX_MCXA_MCXA366._slcd_blink_rate.kSLCD_BlinkRate00 (*C enumerator*), 905
drivers_MCX_MCXA_MCXA366._slcd_blink_rate.kSLCD_BlinkRate01 (*C enumerator*), 905
drivers_MCX_MCXA_MCXA366._slcd_blink_rate.kSLCD_BlinkRate02 (*C enumerator*), 905
drivers_MCX_MCXA_MCXA366._slcd_blink_rate.kSLCD_BlinkRate03 (*C enumerator*), 905
drivers_MCX_MCXA_MCXA366._slcd_blink_rate.kSLCD_BlinkRate04 (*C enumerator*), 905
drivers_MCX_MCXA_MCXA366._slcd_blink_rate.kSLCD_BlinkRate05 (*C enumerator*), 905
drivers_MCX_MCXA_MCXA366._slcd_blink_rate.kSLCD_BlinkRate06 (*C enumerator*), 905
drivers_MCX_MCXA_MCXA366._slcd_blink_rate.kSLCD_BlinkRate07 (*C enumerator*), 905
drivers_MCX_MCXA_MCXA366._slcd_clock_prescaler (*C enum*), 903
drivers_MCX_MCXA_MCXA366._slcd_clock_prescaler.kSLCD_ClkPrescaler00 (*C enumerator*), 903
drivers_MCX_MCXA_MCXA366._slcd_clock_prescaler.kSLCD_ClkPrescaler01 (*C enumerator*), 903
drivers_MCX_MCXA_MCXA366._slcd_clock_prescaler.kSLCD_ClkPrescaler02 (*C enumerator*), 903
drivers_MCX_MCXA_MCXA366._slcd_clock_prescaler.kSLCD_ClkPrescaler03 (*C enumerator*), 903
drivers_MCX_MCXA_MCXA366._slcd_clock_prescaler.kSLCD_ClkPrescaler04 (*C enumerator*), 903
drivers_MCX_MCXA_MCXA366._slcd_clock_prescaler.kSLCD_ClkPrescaler05 (*C enumerator*), 903
drivers_MCX_MCXA_MCXA366._slcd_clock_prescaler.kSLCD_ClkPrescaler06 (*C enumerator*), 903
drivers_MCX_MCXA_MCXA366._slcd_clock_prescaler.kSLCD_ClkPrescaler07 (*C enumerator*), 903
drivers_MCX_MCXA_MCXA366._slcd_config (*C struct*), 910
drivers_MCX_MCXA_MCXA366._slcd_config.backPlaneHighPin (*C var*), 911
drivers_MCX_MCXA_MCXA366._slcd_config.backPlaneLowPin (*C var*), 911
drivers_MCX_MCXA_MCXA366._slcd_config.displayMode (*C var*), 910
drivers_MCX_MCXA_MCXA366._slcd_config.dutyCycle (*C var*), 911
drivers_MCX_MCXA_MCXA366._slcd_config.faultConfig (*C var*), 911
drivers_MCX_MCXA_MCXA366._slcd_config.frameFreqIntEnable (*C var*), 911
drivers_MCX_MCXA_MCXA366._slcd_config.lowPowerBehavior (*C var*), 911
drivers_MCX_MCXA_MCXA366._slcd_config.lowPowerWaveform (*C var*), 910
drivers_MCX_MCXA_MCXA366._slcd_config.sampleHold (*C var*), 910
drivers_MCX_MCXA_MCXA366._slcd_config.slcdHighPinEnabled (*C var*), 911
drivers_MCX_MCXA_MCXA366._slcd_config.slcdLowPinEnabled (*C var*), 911
drivers_MCX_MCXA_MCXA366._slcd_config.voltageTrimVLL1 (*C var*), 910
drivers_MCX_MCXA_MCXA366._slcd_config.voltageTrimVLL2 (*C var*), 910
drivers_MCX_MCXA_MCXA366._slcd_display_mode (*C enum*), 907
drivers_MCX_MCXA_MCXA366._slcd_display_mode.kSLCD_AlternateMode (*C enumerator*), 907

drivers_MCX_MCXA_MCXA366._slcd_display_mode.kSLCD_BlankMode (*C enumerator*), 907
drivers_MCX_MCXA_MCXA366._slcd_display_mode.kSLCD_NormalMode (*C enumerator*), 907
drivers_MCX_MCXA_MCXA366._slcd_duty_cycle (*C enum*), 905
drivers_MCX_MCXA_MCXA366._slcd_duty_cycle.kSLCD_1Div1DutyCycle (*C enumerator*), 906
drivers_MCX_MCXA_MCXA366._slcd_duty_cycle.kSLCD_1Div2DutyCycle (*C enumerator*), 906
drivers_MCX_MCXA_MCXA366._slcd_duty_cycle.kSLCD_1Div3DutyCycle (*C enumerator*), 906
drivers_MCX_MCXA_MCXA366._slcd_duty_cycle.kSLCD_1Div4DutyCycle (*C enumerator*), 906
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_clock_prescaler (*C enum*), 907
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_clock_prescaler.kSLCD_FaultSampleFreqDivider1 (*C enumerator*), 907
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_clock_prescaler.kSLCD_FaultSampleFreqDivider2 (*C enumerator*), 907
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_clock_prescaler.kSLCD_FaultSampleFreqDivider4 (*C enumerator*), 907
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_clock_prescaler.kSLCD_FaultSampleFreqDivider8 (*C enumerator*), 907
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_clock_prescaler.kSLCD_FaultSampleFreqDivider16 (*C enumerator*), 907
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_clock_prescaler.kSLCD_FaultSampleFreqDivider32 (*C enumerator*), 907
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_clock_prescaler.kSLCD_FaultSampleFreqDivider64 (*C enumerator*), 907
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_clock_prescaler.kSLCD_FaultSampleFreqDivider128 (*C enumerator*), 908
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_config (*C struct*), 910
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_config.faultDetectBackPlaneEnable (*C var*), 910
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_config.faultDetectIntEnable (*C var*), 910
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_config.faultDetectPinIndex (*C var*), 910
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_config.faultPrescaler (*C var*), 910
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_config.width (*C var*), 910
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_sample_window_width (*C enum*), 908
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_sample_window_width.kSLCD_FaultDetectWindowWidth4Sa (*C enumerator*), 908
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_sample_window_width.kSLCD_FaultDetectWindowWidth8Sa (*C enumerator*), 908
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_sample_window_width.kSLCD_FaultDetectWindowWidth16S (*C enumerator*), 908
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_sample_window_width.kSLCD_FaultDetectWindowWidth32S (*C enumerator*), 908
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_sample_window_width.kSLCD_FaultDetectWindowWidth64S (*C enumerator*), 908
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_sample_window_width.kSLCD_FaultDetectWindowWidth128 (*C enumerator*), 908
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_sample_window_width.kSLCD_FaultDetectWindowWidth256 (*C enumerator*), 908
drivers_MCX_MCXA_MCXA366._slcd_fault_detect_sample_window_width.kSLCD_FaultDetectWindowWidth512 (*C enumerator*), 908
drivers_MCX_MCXA_MCXA366._slcd_interrupt_enable (*C enum*), 908
drivers_MCX_MCXA_MCXA366._slcd_interrupt_enable.kSLCD_FaultDetectCompleteInterrupt (*C enumerator*), 908
drivers_MCX_MCXA_MCXA366._slcd_interrupt_enable.kSLCD_FrameFreqInterrupt (*C enumerator*), 908
drivers_MCX_MCXA_MCXA366._slcd_lowpower_behavior (*C enum*), 908
drivers_MCX_MCXA_MCXA366._slcd_lowpower_behavior.kSLCD_DisabledInWaitStop (*C enumerator*), 909
drivers_MCX_MCXA_MCXA366._slcd_lowpower_behavior.kSLCD_EnabledInStopOnly (*C enumerator*), 909

drivers_MCX_MCXA_MCXA366._slcd_lowpower_behavior.kSLCD_EnabledInWaitOnly (*C enumerator*), 909
drivers_MCX_MCXA_MCXA366._slcd_lowpower_behavior.kSLCD_EnabledInWaitStop (*C enumerator*), 908
drivers_MCX_MCXA_MCXA366._slcd_phase_index (*C enum*), 906
drivers_MCX_MCXA_MCXA366._slcd_phase_index.kSLCD_PhaseAIndex (*C enumerator*), 906
drivers_MCX_MCXA_MCXA366._slcd_phase_index.kSLCD_PhaseBIndex (*C enumerator*), 906
drivers_MCX_MCXA_MCXA366._slcd_phase_index.kSLCD_PhaseCIndex (*C enumerator*), 906
drivers_MCX_MCXA_MCXA366._slcd_phase_index.kSLCD_PhaseDIndex (*C enumerator*), 906
drivers_MCX_MCXA_MCXA366._slcd_phase_type (*C enum*), 906
drivers_MCX_MCXA_MCXA366._slcd_phase_type.kSLCD_NoPhaseActivate (*C enumerator*), 906
drivers_MCX_MCXA_MCXA366._slcd_phase_type.kSLCD_PhaseAActivate (*C enumerator*), 906
drivers_MCX_MCXA_MCXA366._slcd_phase_type.kSLCD_PhaseBActivate (*C enumerator*), 906
drivers_MCX_MCXA_MCXA366._slcd_phase_type.kSLCD_PhaseCActivate (*C enumerator*), 906
drivers_MCX_MCXA_MCXA366._slcd_phase_type.kSLCD_PhaseDActivate (*C enumerator*), 906
drivers_MCX_MCXA_MCXA366._slcd_regulated_voltage_trim (*C enum*), 904
drivers_MCX_MCXA_MCXA366._slcd_regulated_voltage_trim.kSLCD_VolatgeTrimDecrease50mV (*C enumerator*), 905
drivers_MCX_MCXA_MCXA366._slcd_regulated_voltage_trim.kSLCD_VolatgeTrimDecrease100mV (*C enumerator*), 904
drivers_MCX_MCXA_MCXA366._slcd_regulated_voltage_trim.kSLCD_VolatgeTrimDecrease150mV (*C enumerator*), 904
drivers_MCX_MCXA_MCXA366._slcd_regulated_voltage_trim.kSLCD_VolatgeTrimDecrease200mV (*C enumerator*), 904
drivers_MCX_MCXA_MCXA366._slcd_regulated_voltage_trim.kSLCD_VolatgeTrimDecrease250mV (*C enumerator*), 904
drivers_MCX_MCXA_MCXA366._slcd_regulated_voltage_trim.kSLCD_VolatgeTrimDecrease300mV (*C enumerator*), 904
drivers_MCX_MCXA_MCXA366._slcd_regulated_voltage_trim.kSLCD_VolatgeTrimDecrease350mV (*C enumerator*), 904
drivers_MCX_MCXA_MCXA366._slcd_regulated_voltage_trim.kSLCD_VolatgeTrimDecrease400mV (*C enumerator*), 904
drivers_MCX_MCXA_MCXA366._slcd_regulated_voltage_trim.kSLCD_VolatgeTrimIncrease50mV (*C enumerator*), 904
drivers_MCX_MCXA_MCXA366._slcd_regulated_voltage_trim.kSLCD_VolatgeTrimIncrease100mV (*C enumerator*), 904
drivers_MCX_MCXA_MCXA366._slcd_regulated_voltage_trim.kSLCD_VolatgeTrimIncrease150mV (*C enumerator*), 904
drivers_MCX_MCXA_MCXA366._slcd_regulated_voltage_trim.kSLCD_VolatgeTrimIncrease200mV (*C enumerator*), 904
drivers_MCX_MCXA_MCXA366._slcd_regulated_voltage_trim.kSLCD_VolatgeTrimIncrease250mV (*C enumerator*), 904
drivers_MCX_MCXA_MCXA366._slcd_regulated_voltage_trim.kSLCD_VolatgeTrimIncrease300mV (*C enumerator*), 904
drivers_MCX_MCXA_MCXA366._slcd_regulated_voltage_trim.kSLCD_VolatgeTrimIncrease350mV (*C enumerator*), 904
drivers_MCX_MCXA_MCXA366._slcd_regulated_voltage_trim.kSLCD_VolatgeTrimNo (*C enumerator*), 904
drivers_MCX_MCXA_MCXA366._slcd_sample_hold (*C enum*), 905
drivers_MCX_MCXA_MCXA366._slcd_sample_hold.kSLCD_SampleHold64Cycle (*C enumerator*), 905
drivers_MCX_MCXA_MCXA366._slcd_sample_hold.kSLCD_SampleHold128Cycle (*C enumerator*), 905
drivers_MCX_MCXA_MCXA366._slcd_sample_hold.kSLCD_SampleHoldNone (*C enumerator*), 905
drivers_MCX_MCXA_MCXA366._smartdma_camera_api (*C enum*), 913
drivers_MCX_MCXA_MCXA366._smartdma_camera_api.kSMARTDMA_CameraDiv4FrameQVGAGrayScale (*C enumerator*), 914

drivers_MCX_MCXA_MCXA366._smartdma_camera_api.kSMARTDMA_CameraDiv16Frame384_384 (*C enumerator*), 914
drivers_MCX_MCXA_MCXA366._smartdma_camera_api.kSMARTDMA_CameraDiv16FrameQVGA (*C enumerator*), 913
drivers_MCX_MCXA_MCXA366._smartdma_camera_api.kSMARTDMA_CameraDiv16FrameQVGAGrayScale (*C enumerator*), 914
drivers_MCX_MCXA_MCXA366._smartdma_camera_api.kSMARTDMA_CameraWholeFrame320_480 (*C enumerator*), 914
drivers_MCX_MCXA_MCXA366._smartdma_camera_api.kSMARTDMA_CameraWholeFrame480_320 (*C enumerator*), 914
drivers_MCX_MCXA_MCXA366._smartdma_camera_api.kSMARTDMA_CameraWholeFrameQVGA (*C enumerator*), 913
drivers_MCX_MCXA_MCXA366._smartdma_camera_api.kSMARTDMA_FlexIO_CameraDiv16Frame (*C enumerator*), 913
drivers_MCX_MCXA_MCXA366._smartdma_camera_api.kSMARTDMA_FlexIO_CameraWholeFrame (*C enumerator*), 913
drivers_MCX_MCXA_MCXA366._smartdma_camera_param (*C struct*), 916
drivers_MCX_MCXA_MCXA366._smartdma_display_api (*C enum*), 913
drivers_MCX_MCXA_MCXA366._smartdma_display_api.kSMARTDMA_FlexIO_DMA (*C enumerator*), 913
drivers_MCX_MCXA_MCXA366._smartdma_flexio_mculcd_param (*C struct*), 916
drivers_MCX_MCXA_MCXA366._smartdma_keyscan_4x4_param (*C struct*), 916
drivers_MCX_MCXA_MCXA366._smartdma_keyscan_api (*C enum*), 914
drivers_MCX_MCXA_MCXA366._smartdma_keyscan_api.kSMARTDMA_Keyscan_4x4 (*C enumerator*), 914
drivers_MCX_MCXA_MCXA366._spc_active_mode_core_ldo_option (*C struct*), 819
drivers_MCX_MCXA_MCXA366._spc_active_mode_core_ldo_option.CoreLDODriveStrength (*C var*), 820
drivers_MCX_MCXA_MCXA366._spc_active_mode_core_ldo_option.CoreLDOVoltage (*C var*), 820
drivers_MCX_MCXA_MCXA366._spc_active_mode_dcdc_option (*C struct*), 820
drivers_MCX_MCXA_MCXA366._spc_active_mode_dcdc_option.DCDCDriveStrength (*C var*), 820
drivers_MCX_MCXA_MCXA366._spc_active_mode_dcdc_option.DCDCVoltage (*C var*), 820
drivers_MCX_MCXA_MCXA366._spc_active_mode_regulators_config (*C struct*), 822
drivers_MCX_MCXA_MCXA366._spc_active_mode_regulators_config.bandgapMode (*C var*), 823
drivers_MCX_MCXA_MCXA366._spc_active_mode_regulators_config.CoreLDOOption (*C var*), 823
drivers_MCX_MCXA_MCXA366._spc_active_mode_regulators_config.DCDCOption (*C var*), 823
drivers_MCX_MCXA_MCXA366._spc_active_mode_regulators_config.lpBuff (*C var*), 823
drivers_MCX_MCXA_MCXA366._spc_active_mode_regulators_config.SysLDOOption (*C var*), 823
drivers_MCX_MCXA_MCXA366._spc_active_mode_sys_ldo_option (*C struct*), 820
drivers_MCX_MCXA_MCXA366._spc_active_mode_sys_ldo_option.SysLDODriveStrength (*C var*), 820
drivers_MCX_MCXA_MCXA366._spc_active_mode_sys_ldo_option.SysLDOVoltage (*C var*), 820
drivers_MCX_MCXA_MCXA366._spc_analog_module_control (*C enum*), 811
drivers_MCX_MCXA_MCXA366._spc_analog_module_control.kSPC_controlAllModules (*C enumerator*), 813
drivers_MCX_MCXA_MCXA366._spc_analog_module_control.kSPC_controlCmp0 (*C enumerator*), 812
drivers_MCX_MCXA_MCXA366._spc_analog_module_control.kSPC_controlCmp0Dac (*C enumerator*), 812
drivers_MCX_MCXA_MCXA366._spc_analog_module_control.kSPC_controlCmp1 (*C enumerator*), 812
drivers_MCX_MCXA_MCXA366._spc_analog_module_control.kSPC_controlCmp1Dac (*C enumerator*), 812
drivers_MCX_MCXA_MCXA366._spc_analog_module_control.kSPC_controlCmp2 (*C enumerator*), 812

drivers_MCX_MCXA_MCXA366._spc_analog_module_control.kSPC_controlCmp2Dac (*C enumerator*), 812
drivers_MCX_MCXA_MCXA366._spc_analog_module_control.kSPC_controlDac0 (*C enumerator*), 812
drivers_MCX_MCXA_MCXA366._spc_analog_module_control.kSPC_controlDac1 (*C enumerator*), 812
drivers_MCX_MCXA_MCXA366._spc_analog_module_control.kSPC_controlDac2 (*C enumerator*), 812
drivers_MCX_MCXA_MCXA366._spc_analog_module_control.kSPC_controlOpamp0 (*C enumerator*), 812
drivers_MCX_MCXA_MCXA366._spc_analog_module_control.kSPC_controlOpamp1 (*C enumerator*), 812
drivers_MCX_MCXA_MCXA366._spc_analog_module_control.kSPC_controlOpamp2 (*C enumerator*), 812
drivers_MCX_MCXA_MCXA366._spc_analog_module_control.kSPC_controlOpamp3 (*C enumerator*), 812
drivers_MCX_MCXA_MCXA366._spc_analog_module_control.kSPC_controlTsi0 (*C enumerator*), 812
drivers_MCX_MCXA_MCXA366._spc_analog_module_control.kSPC_controlUsb3vDet (*C enumerator*), 812
drivers_MCX_MCXA_MCXA366._spc_analog_module_control.kSPC_controlVbat (*C enumerator*), 812
drivers_MCX_MCXA_MCXA366._spc_analog_module_control.kSPC_controlVref (*C enumerator*), 811
drivers_MCX_MCXA_MCXA366._spc_bandgap_mode (*C enum*), 814
drivers_MCX_MCXA_MCXA366._spc_bandgap_mode.kSPC_BandgapDisabled (*C enumerator*), 814
drivers_MCX_MCXA_MCXA366._spc_bandgap_mode.kSPC_BandgapEnabledBufferDisabled (*C enumerator*), 814
drivers_MCX_MCXA_MCXA366._spc_bandgap_mode.kSPC_BandgapEnabledBufferEnabled (*C enumerator*), 814
drivers_MCX_MCXA_MCXA366._spc_bandgap_mode.kSPC_BandgapReserved (*C enumerator*), 814
drivers_MCX_MCXA_MCXA366._spc_core_ldo_drive_strength (*C enum*), 816
drivers_MCX_MCXA_MCXA366._spc_core_ldo_drive_strength.kSPC_CoreLDO_LowDriveStrength (*C enumerator*), 816
drivers_MCX_MCXA_MCXA366._spc_core_ldo_drive_strength.kSPC_CoreLDO_NormalDriveStrength (*C enumerator*), 816
drivers_MCX_MCXA_MCXA366._spc_core_ldo_voltage_level (*C enum*), 815
drivers_MCX_MCXA_MCXA366._spc_core_ldo_voltage_level.kSPC_Core_LDO_RetentionVoltage (*C enumerator*), 815
drivers_MCX_MCXA_MCXA366._spc_core_ldo_voltage_level.kSPC_CoreLDO_MidDriveVoltage (*C enumerator*), 816
drivers_MCX_MCXA_MCXA366._spc_core_ldo_voltage_level.kSPC_CoreLDO_NormalVoltage (*C enumerator*), 816
drivers_MCX_MCXA_MCXA366._spc_core_ldo_voltage_level.kSPC_CoreLDO_OverDriveVoltage (*C enumerator*), 816
drivers_MCX_MCXA_MCXA366._spc_core_ldo_voltage_level.kSPC_CoreLDO_UnderDriveVoltage (*C enumerator*), 815
drivers_MCX_MCXA_MCXA366._spc_core_voltage_detect_config (*C struct*), 822
drivers_MCX_MCXA_MCXA366._spc_core_voltage_detect_config.option (*C var*), 822
drivers_MCX_MCXA_MCXA366._spc_dcdc_burst_config (*C struct*), 821
drivers_MCX_MCXA_MCXA366._spc_dcdc_burst_config.externalBurstRequest (*C var*), 821
drivers_MCX_MCXA_MCXA366._spc_dcdc_burst_config.freq (*C var*), 821
drivers_MCX_MCXA_MCXA366._spc_dcdc_burst_config.sofwareBurstRequest (*C var*), 821
drivers_MCX_MCXA_MCXA366._spc_dcdc_burst_config.stabilizeBurstFreq (*C var*), 821
drivers_MCX_MCXA_MCXA366._spc_dcdc_drive_strength (*C enum*), 814
drivers_MCX_MCXA_MCXA366._spc_dcdc_drive_strength.kSPC_DCDC_LowDriveStrength (*C*

enumerator), 815
drivers_MCX_MCXA_MCXA366._spc_dcdc_drive_strength.kSPC_DCDC_NormalDriveStrength (*C enumerator*), 815
drivers_MCX_MCXA_MCXA366._spc_dcdc_drive_strength.kSPC_DCDC_PulseRefreshMode (*C enumerator*), 815
drivers_MCX_MCXA_MCXA366._spc_dcdc_voltage_level (*C enum*), 814
drivers_MCX_MCXA_MCXA366._spc_dcdc_voltage_level.kSPC_DCDC_MidVoltage (*C enumerator*), 814
drivers_MCX_MCXA_MCXA366._spc_dcdc_voltage_level.kSPC_DCDC_NormalVoltage (*C enumerator*), 814
drivers_MCX_MCXA_MCXA366._spc_dcdc_voltage_level.kSPC_DCDC_OverdriveVoltage (*C enumerator*), 814
drivers_MCX_MCXA_MCXA366._spc_dcdc_voltage_level.kSPC_DCDC_RetentionVoltage (*C enumerator*), 814
drivers_MCX_MCXA_MCXA366._spc_io_voltage_detect_config (*C struct*), 822
drivers_MCX_MCXA_MCXA366._spc_io_voltage_detect_config.level (*C var*), 822
drivers_MCX_MCXA_MCXA366._spc_io_voltage_detect_config.option (*C var*), 822
drivers_MCX_MCXA_MCXA366._spc_low_voltage_level_select (*C enum*), 816
drivers_MCX_MCXA_MCXA366._spc_low_voltage_level_select.kSPC_LowVoltageHighRange (*C enumerator*), 816
drivers_MCX_MCXA_MCXA366._spc_low_voltage_level_select.kSPC_LowVoltageLowRange (*C enumerator*), 816
drivers_MCX_MCXA_MCXA366._spc_low_voltage_level_select.kSPC_LowVoltageNormalLevel (*C enumerator*), 816
drivers_MCX_MCXA_MCXA366._spc_low_voltage_level_select.kSPC_LowVoltageSafeLevel (*C enumerator*), 816
drivers_MCX_MCXA_MCXA366._spc_lowpower_mode_core_ldo_option (*C struct*), 820
drivers_MCX_MCXA_MCXA366._spc_lowpower_mode_core_ldo_option.CoreLDODriveStrength (*C var*), 820
drivers_MCX_MCXA_MCXA366._spc_lowpower_mode_core_ldo_option.CoreLDOVoltage (*C var*), 820
drivers_MCX_MCXA_MCXA366._spc_lowpower_mode_dcdc_option (*C struct*), 821
drivers_MCX_MCXA_MCXA366._spc_lowpower_mode_dcdc_option.DCDCDriveStrength (*C var*), 821
drivers_MCX_MCXA_MCXA366._spc_lowpower_mode_dcdc_option.DCDCVoltage (*C var*), 821
drivers_MCX_MCXA_MCXA366._spc_lowpower_mode_regulators_config (*C struct*), 823
drivers_MCX_MCXA_MCXA366._spc_lowpower_mode_regulators_config.bandgapMode (*C var*), 823
drivers_MCX_MCXA_MCXA366._spc_lowpower_mode_regulators_config.CoreIVS (*C var*), 823
drivers_MCX_MCXA_MCXA366._spc_lowpower_mode_regulators_config.CoreLDOOption (*C var*), 823
drivers_MCX_MCXA_MCXA366._spc_lowpower_mode_regulators_config.DCDCOption (*C var*), 823
drivers_MCX_MCXA_MCXA366._spc_lowpower_mode_regulators_config.lpBuff (*C var*), 823
drivers_MCX_MCXA_MCXA366._spc_lowpower_mode_regulators_config.lpIREF (*C var*), 823
drivers_MCX_MCXA_MCXA366._spc_lowpower_mode_regulators_config.SysLDOOption (*C var*), 823
drivers_MCX_MCXA_MCXA366._spc_lowpower_mode_sys_ldo_option (*C struct*), 820
drivers_MCX_MCXA_MCXA366._spc_lowpower_mode_sys_ldo_option.SysLDODriveStrength (*C var*), 821
drivers_MCX_MCXA_MCXA366._spc_lowpower_request_config (*C struct*), 819
drivers_MCX_MCXA_MCXA366._spc_lowpower_request_config.enable (*C var*), 819
drivers_MCX_MCXA_MCXA366._spc_lowpower_request_config.override (*C var*), 819
drivers_MCX_MCXA_MCXA366._spc_lowpower_request_config.polarity (*C var*), 819
drivers_MCX_MCXA_MCXA366._spc_lowPower_request_output_override (*C enum*), 813
drivers_MCX_MCXA_MCXA366._spc_lowPower_request_output_override.kSPC_LowPowerRequestForcedHigh (*C enumerator*), 814
drivers_MCX_MCXA_MCXA366._spc_lowPower_request_output_override.kSPC_LowPowerRequestForcedLow

(*C enumerator*), 814
drivers_MCX_MCXA_MCXA366._spc_lowPower_request_output_override.kSPC_LowPowerRequestNotForced (*C enumerator*), 813
drivers_MCX_MCXA_MCXA366._spc_lowPower_request_output_override.kSPC_LowPowerRequestReserved (*C enumerator*), 814
drivers_MCX_MCXA_MCXA366._spc_lowPower_request_pin_polarity (*C enum*), 813
drivers_MCX_MCXA_MCXA366._spc_lowPower_request_pin_polarity.kSPC_HighTruePolarity (*C enumerator*), 813
drivers_MCX_MCXA_MCXA366._spc_lowPower_request_pin_polarity.kSPC_LowTruePolarity (*C enumerator*), 813
drivers_MCX_MCXA_MCXA366._spc_power_domain_id (*C enum*), 813
drivers_MCX_MCXA_MCXA366._spc_power_domain_id.kSPC_PowerDomain0 (*C enumerator*), 813
drivers_MCX_MCXA_MCXA366._spc_power_domain_id.kSPC_PowerDomain1 (*C enumerator*), 813
drivers_MCX_MCXA_MCXA366._spc_power_domain_low_power_mode (*C enum*), 813
drivers_MCX_MCXA_MCXA366._spc_power_domain_low_power_mode.kSPC_DeepPowerDownWithSysClockOff (*C enumerator*), 813
drivers_MCX_MCXA_MCXA366._spc_power_domain_low_power_mode.kSPC_DeepSleepWithSysClockOff (*C enumerator*), 813
drivers_MCX_MCXA_MCXA366._spc_power_domain_low_power_mode.kSPC_PowerDownWithSysClockOff (*C enumerator*), 813
drivers_MCX_MCXA_MCXA366._spc_power_domain_low_power_mode.kSPC_SleepWithSYSClockRunning (*C enumerator*), 813
drivers_MCX_MCXA_MCXA366._spc_power_domains (*C enum*), 811
drivers_MCX_MCXA_MCXA366._spc_power_domains.kSPC_MAINPowerDomainRetain (*C enumerator*), 811
drivers_MCX_MCXA_MCXA366._spc_power_domains.kSPC_WAKEPowerDomainRetain (*C enumerator*), 811
drivers_MCX_MCXA_MCXA366._spc_sram_operate_voltage (*C enum*), 816
drivers_MCX_MCXA_MCXA366._spc_sram_operate_voltage.kSPC_sramOperateAt1P0V (*C enumerator*), 816
drivers_MCX_MCXA_MCXA366._spc_sram_operate_voltage.kSPC_sramOperateAt1P1V (*C enumerator*), 817
drivers_MCX_MCXA_MCXA366._spc_sram_operate_voltage.kSPC_sramOperateAt1P2V (*C enumerator*), 817
drivers_MCX_MCXA_MCXA366._spc_sram_voltage_config (*C struct*), 819
drivers_MCX_MCXA_MCXA366._spc_sram_voltage_config.operateVoltage (*C var*), 819
drivers_MCX_MCXA_MCXA366._spc_sram_voltage_config.requestVoltageUpdate (*C var*), 819
drivers_MCX_MCXA_MCXA366._spc_sys_ldo_drive_strength (*C enum*), 815
drivers_MCX_MCXA_MCXA366._spc_sys_ldo_drive_strength.kSPC_SysLDO_LowDriveStrength (*C enumerator*), 815
drivers_MCX_MCXA_MCXA366._spc_sys_ldo_drive_strength.kSPC_SysLDO_NormalDriveStrength (*C enumerator*), 815
drivers_MCX_MCXA_MCXA366._spc_sys_ldo_voltage_level (*C enum*), 815
drivers_MCX_MCXA_MCXA366._spc_sys_ldo_voltage_level.kSPC_SysLDO_NormalVoltage (*C enumerator*), 815
drivers_MCX_MCXA_MCXA366._spc_sys_ldo_voltage_level.kSPC_SysLDO_OverDriveVoltage (*C enumerator*), 815
drivers_MCX_MCXA_MCXA366._spc_system_voltage_detect_config (*C struct*), 822
drivers_MCX_MCXA_MCXA366._spc_system_voltage_detect_config.level (*C var*), 822
drivers_MCX_MCXA_MCXA366._spc_system_voltage_detect_config.option (*C var*), 822
drivers_MCX_MCXA_MCXA366._spc_voltage_detect_flags (*C enum*), 811
drivers_MCX_MCXA_MCXA366._spc_voltage_detect_flags.kSPC_CoreVDDHighVoltageDetectFlag (*C enumerator*), 811
drivers_MCX_MCXA_MCXA366._spc_voltage_detect_flags.kSPC_CoreVDDLowVoltageDetectFlag (*C enumerator*), 811
drivers_MCX_MCXA_MCXA366._spc_voltage_detect_flags.kSPC_IOVDDHighVoltageDetectFlag

(*C enumerator*), 811
drivers_MCX_MCXA_MCXA366._spc_voltage_detect_flags.kSPC_IOVDDLowVoltageDetectFlag (*C enumerator*), 811
drivers_MCX_MCXA_MCXA366._spc_voltage_detect_flags.kSPC_SystemVDDHighVoltageDetectFlag (*C enumerator*), 811
drivers_MCX_MCXA_MCXA366._spc_voltage_detect_flags.kSPC_SystemVDDLowVoltageDetectFlag (*C enumerator*), 811
drivers_MCX_MCXA_MCXA366._spc_voltage_detect_option (*C struct*), 821
drivers_MCX_MCXA_MCXA366._spc_voltage_detect_option.HVDInterruptEnable (*C var*), 821
drivers_MCX_MCXA_MCXA366._spc_voltage_detect_option.HVDResetEnable (*C var*), 821
drivers_MCX_MCXA_MCXA366._spc_voltage_detect_option.LVDInterruptEnable (*C var*), 822
drivers_MCX_MCXA_MCXA366._spc_voltage_detect_option.LVDResetEnable (*C var*), 822
drivers_MCX_MCXA_MCXA366._status_groups (*C enum*), 618
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_AON_COMMON (*C enumerator*), 626
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_AON_POWER (*C enumerator*), 626
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_ApplicationRangeStart (*C enumerator*), 623
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_ASRC (*C enumerator*), 625
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_AUDMIX (*C enumerator*), 623
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_BMA (*C enumerator*), 626
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_BUTTON (*C enumerator*), 624
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_CAAM (*C enumerator*), 621
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_CLIF (*C enumerator*), 626
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_CODEC (*C enumerator*), 625
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_COMMON_TASK (*C enumerator*), 625
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_CSI (*C enumerator*), 620
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_CSS_PKC (*C enumerator*), 626
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_DCP (*C enumerator*), 622
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_DebugConsole (*C enumerator*), 623
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_DMA (*C enumerator*), 621
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_DMAMGR (*C enumerator*), 621
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_DMIC (*C enumerator*), 621
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_DSPI (*C enumerator*), 619
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_ECSPI (*C enumerator*), 621
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_EDMA (*C enumerator*), 621
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_ELA_CSEC (*C enumerator*), 626
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_ELE (*C enumerator*), 626
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_ELEMU (*C enumerator*), 625
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_ELS_PKC (*C enumerator*), 626
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_ENDAT3 (*C enumerator*), 626
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_ENET (*C enumerator*), 620
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_ENET_QOS (*C enumerator*), 625
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_ESAI (*C enumerator*), 622
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_EVENT_CTRL (*C enumerator*), 627
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_EXTERN_EEPROM (*C enumerator*), 624
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_FLASH (*C enumerator*), 618
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_FLASHIAP (*C enumerator*), 620
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_FLEXCAN (*C enumerator*), 621
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_FLEXCOMM_I2C (*C enumerator*), 620
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_FLEXIO_A_FORMAT (*C enumerator*), 627

drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_FLEXIO_CAMERA (*C enumerator*), 621
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_FLEXIO_I2C (*C enumerator*), 619
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_FLEXIO_I2S (*C enumerator*), 620
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_FLEXIO_MCULCD (*C enumerator*), 620
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_FLEXIO_SPI (*C enumerator*), 618
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_FLEXIO_T_FORMAT (*C enumerator*), 627
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_FLEXIO_UART (*C enumerator*), 619
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_FLEXSPI (*C enumerator*), 622
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_Generic (*C enumerator*), 618
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_GLIKEY (*C enumerator*), 626
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_HAL_ADC_SENSOR (*C enumerator*), 624
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_HAL_FLASH (*C enumerator*), 624
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_HAL_GPIO (*C enumerator*), 623
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_HAL_I2C (*C enumerator*), 624
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_HAL_I2S (*C enumerator*), 624
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_HAL_PWM (*C enumerator*), 624
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_HAL_RNG (*C enumerator*), 624
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_HAL_SPI (*C enumerator*), 624
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_HAL_TIMER (*C enumerator*), 624
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_HAL_UART (*C enumerator*), 623
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_HASHCRYPT (*C enumerator*), 622
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_HIPERFACE (*C enumerator*), 626
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_HOSTIF (*C enumerator*), 626
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_I2C (*C enumerator*), 619
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_I2S (*C enumerator*), 620
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_I3C (*C enumerator*), 622
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_I3CBUS (*C enumerator*), 625
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_IAP (*C enumerator*), 623
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_ICS (*C enumerator*), 622
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_IPED (*C enumerator*), 626
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_IUART (*C enumerator*), 620
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_JPEGDEC (*C enumerator*), 623
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_LED (*C enumerator*), 624
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_LIST (*C enumerator*), 624
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_LMEM (*C enumerator*), 620
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_LOG (*C enumerator*), 625
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_LPC_I2C (*C enumerator*), 622
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_LPC_I2C_1 (*C enumerator*), 622
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_LPC_MINISPI (*C enumerator*), 622
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_LPC_QSPI (*C enumerator*), 627
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_LPC_SPI (*C enumerator*), 621
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_LPC_SPI_SSP (*C enumerator*), 622
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_LPC_USART (*C enumerator*), 621
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_LPI2C (*C enumerator*), 619
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_LPSCI (*C enumerator*), 619
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_LPSPI (*C enumerator*), 618

drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_LPUART (*C enumerator*), 619
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_LTC (*C enumerator*), 621
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_MCAN (*C enumerator*), 621
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_MCG (*C enumerator*), 619
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_MECC (*C enumerator*), 625
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_MEM_MANAGER (*C enumerator*), 624
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_MIPI_DSI (*C enumerator*), 620
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_MMDC (*C enumerator*), 622
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_MSCAN (*C enumerator*), 622
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_MSG (*C enumerator*), 625
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_NETC (*C enumerator*), 626
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_NOTIFIER (*C enumerator*), 623
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_NPX (*C enumerator*), 626
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_OSA (*C enumerator*), 625
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_OTFAD (*C enumerator*), 625
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_OTP (*C enumerator*), 621
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_PDM (*C enumerator*), 622
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_PHY (*C enumerator*), 620
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_PNGDEC (*C enumerator*), 623
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_POWER (*C enumerator*), 620
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_POWER_MANAGER (*C enumerator*), 626
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_PUF (*C enumerator*), 623
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_QSCI (*C enumerator*), 625
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_QSPI (*C enumerator*), 621
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_QUEUEDSPI (*C enumerator*), 625
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SAI (*C enumerator*), 619
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SCG (*C enumerator*), 619
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SDHC (*C enumerator*), 619
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SDIF (*C enumerator*), 621
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SDIOSLV (*C enumerator*), 625
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SDK_FLEXSPINOR (*C enumerator*), 625
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SDK_OCOTP (*C enumerator*), 625
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SDMA (*C enumerator*), 622
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SDMMC (*C enumerator*), 619
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SDRAMC (*C enumerator*), 620
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SDSPI (*C enumerator*), 620
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SEMA42 (*C enumerator*), 619
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SEMC (*C enumerator*), 623
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SERIALMANAGER (*C enumerator*), 624
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SFA (*C enumerator*), 623
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SHELL (*C enumerator*), 624
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SMARTCARD (*C enumerator*), 620
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SPC (*C enumerator*), 623
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SPDIF (*C enumerator*), 622
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SPI (*C enumerator*), 619
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_SPIFI (*C enumerator*), 621
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_TIMERMANAGER (*C enumerator*), 624
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_TOUCH_PANEL (*C enumerator*), 623
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_TRGMUX (*C enumerator*), 620
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_UART (*C enumerator*), 619

drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_USDHC (*C enumerator*), 622
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_VBAT (*C enumerator*), 623
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_XRDC (*C enumerator*), 619
drivers_MCX_MCXA_MCXA366._status_groups.kStatusGroup_XSPI (*C enumerator*), 623
drivers_MCX_MCXA_MCXA366._tdet_active_tamper_clock (*C enum*), 921
drivers_MCX_MCXA_MCXA366._tdet_active_tamper_clock.kTDET_ClockType1Hz (*C enumerator*), 921
drivers_MCX_MCXA_MCXA366._tdet_active_tamper_clock.kTDET_ClockType64Hz (*C enumerator*), 921
drivers_MCX_MCXA_MCXA366._tdet_active_tamper_config (*C struct*), 930
drivers_MCX_MCXA_MCXA366._tdet_active_tamper_config.activeTamperPolynomial (*C var*), 930
drivers_MCX_MCXA_MCXA366._tdet_active_tamper_config.activeTamperShift (*C var*), 930
drivers_MCX_MCXA_MCXA366._tdet_active_tamper_register (*C enum*), 924
drivers_MCX_MCXA_MCXA366._tdet_active_tamper_register.kTDET_ActiveTamperRegister0 (*C enumerator*), 924
drivers_MCX_MCXA_MCXA366._tdet_active_tamper_register.kTDET_ActiveTamperRegister1 (*C enumerator*), 924
drivers_MCX_MCXA_MCXA366._tdet_config (*C struct*), 928
drivers_MCX_MCXA_MCXA366._tdet_config.clockSourceActiveTamper0 (*C var*), 928
drivers_MCX_MCXA_MCXA366._tdet_config.clockSourceActiveTamper1 (*C var*), 928
drivers_MCX_MCXA_MCXA366._tdet_config.disablePrescalerAfterTamper (*C var*), 929
drivers_MCX_MCXA_MCXA366._tdet_config.innerClockAndPrescalerEnable (*C var*), 928
drivers_MCX_MCXA_MCXA366._tdet_config.prescaler (*C var*), 929
drivers_MCX_MCXA_MCXA366._tdet_config.tamperForceSystemResetEnable (*C var*), 928
drivers_MCX_MCXA_MCXA366._tdet_config.updateMode (*C var*), 928
drivers_MCX_MCXA_MCXA366._tdet_external_tamper_pin (*C enum*), 923
drivers_MCX_MCXA_MCXA366._tdet_external_tamper_pin.kTDET_ExternalTamper0 (*C enumerator*), 923
drivers_MCX_MCXA_MCXA366._tdet_external_tamper_pin.kTDET_ExternalTamper1 (*C enumerator*), 924
drivers_MCX_MCXA_MCXA366._tdet_external_tamper_pin.kTDET_ExternalTamper2 (*C enumerator*), 924
drivers_MCX_MCXA_MCXA366._tdet_external_tamper_pin.kTDET_ExternalTamper3 (*C enumerator*), 924
drivers_MCX_MCXA_MCXA366._tdet_external_tamper_pin.kTDET_ExternalTamper4 (*C enumerator*), 924
drivers_MCX_MCXA_MCXA366._tdet_external_tamper_pin.kTDET_ExternalTamper5 (*C enumerator*), 924
drivers_MCX_MCXA_MCXA366._tdet_external_tamper_pin.kTDET_ExternalTamper6 (*C enumerator*), 924
drivers_MCX_MCXA_MCXA366._tdet_external_tamper_pin.kTDET_ExternalTamper7 (*C enumerator*), 924
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_expected (*C enum*), 923
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_expected.kTDET_GlitchFilterExpectedActTamperOut0 (*C enumerator*), 923
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_expected.kTDET_GlitchFilterExpectedActTamperOut1 (*C enumerator*), 923
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_expected.kTDET_GlitchFilterExpectedActTamperOutXOR (*C enumerator*), 923
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_expected.kTDET_GlitchFilterExpectedLogicZero (*C enumerator*), 923
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_prescaler (*C enum*), 923
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_prescaler.kTDET_GlitchFilterClock512Hz (*C enumerator*), 923
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_prescaler.kTDET_GlitchFilterClock32768Hz (*C enumerator*), 923
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_pull (*C enum*), 923
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_pull.kTDET_GlitchFilterPullTypeAssert (*C*

enumerator), 923
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_pull.kTDET_GlitchFilterPullTypeNegate (*C enumerator*), 923
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_sample_freq (*C enum*), 922
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_sample_freq.kTDET_GlitchFilterSamplingEveryCycle8 (*C enumerator*), 922
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_sample_freq.kTDET_GlitchFilterSamplingEveryCycle32 (*C enumerator*), 922
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_sample_freq.kTDET_GlitchFilterSamplingEveryCycle128 (*C enumerator*), 922
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_sample_freq.kTDET_GlitchFilterSamplingEveryCycle512 (*C enumerator*), 922
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_sample_width (*C enum*), 922
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_sample_width.kTDET_GlitchFilterSampleCycle2 (*C enumerator*), 922
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_sample_width.kTDET_GlitchFilterSampleCycle4 (*C enumerator*), 922
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_sample_width.kTDET_GlitchFilterSampleCycle8 (*C enumerator*), 922
drivers_MCX_MCXA_MCXA366._tdet_glitch_filter_sample_width.kTDET_GlitchFilterSampleDisable (*C enumerator*), 922
drivers_MCX_MCXA_MCXA366._tdet_interrupt (*C enum*), 925
drivers_MCX_MCXA_MCXA366._tdet_interrupt.kTDET_InterruptAll (*C enumerator*), 925
drivers_MCX_MCXA_MCXA366._tdet_interrupt.kTDET_InterruptTamper (*C enumerator*), 925
drivers_MCX_MCXA_MCXA366._tdet_interrupt.kTDET_InterruptTamperPinTamper0 (*C enumerator*), 925
drivers_MCX_MCXA_MCXA366._tdet_interrupt.kTDET_InterruptTamperPinTamper1 (*C enumerator*), 925
drivers_MCX_MCXA_MCXA366._tdet_interrupt.kTDET_InterruptTamperPinTamper_All (*C enumerator*), 925
drivers_MCX_MCXA_MCXA366._tdet_interrupt.kTDET_InterruptTIF0 (*C enumerator*), 925
drivers_MCX_MCXA_MCXA366._tdet_pin_config (*C struct*), 929
drivers_MCX_MCXA_MCXA366._tdet_pin_config.glitchFilterEnable (*C var*), 929
drivers_MCX_MCXA_MCXA366._tdet_pin_config.glitchFilterPrescaler (*C var*), 929
drivers_MCX_MCXA_MCXA366._tdet_pin_config.glitchFilterWidth (*C var*), 929
drivers_MCX_MCXA_MCXA366._tdet_pin_config.pinDirection (*C var*), 929
drivers_MCX_MCXA_MCXA366._tdet_pin_config.pinPolarity (*C var*), 929
drivers_MCX_MCXA_MCXA366._tdet_pin_config.tamperPinExpected (*C var*), 929
drivers_MCX_MCXA_MCXA366._tdet_pin_config.tamperPinSampleFrequency (*C var*), 929
drivers_MCX_MCXA_MCXA366._tdet_pin_config.tamperPinSampleWidth (*C var*), 929
drivers_MCX_MCXA_MCXA366._tdet_pin_config.tamperPullEnable (*C var*), 929
drivers_MCX_MCXA_MCXA366._tdet_pin_config.tamperPullSelect (*C var*), 929
drivers_MCX_MCXA_MCXA366._tdet_pin_direction (*C enum*), 922
drivers_MCX_MCXA_MCXA366._tdet_pin_direction.kTDET_TamperPinDirectionIn (*C enumerator*), 922
drivers_MCX_MCXA_MCXA366._tdet_pin_direction.kTDET_TamperPinDirectionOut (*C enumerator*), 922
drivers_MCX_MCXA_MCXA366._tdet_pin_polarity (*C enum*), 921
drivers_MCX_MCXA_MCXA366._tdet_pin_polarity.kTDET_TamperPinPolarityExpectInverted (*C enumerator*), 921
drivers_MCX_MCXA_MCXA366._tdet_pin_polarity.kTDET_TamperPinPolarityExpectNormal (*C enumerator*), 921
drivers_MCX_MCXA_MCXA366._tdet_register (*C enum*), 925
drivers_MCX_MCXA_MCXA366._tdet_register.kTDET_AllRegisters (*C enumerator*), 926
drivers_MCX_MCXA_MCXA366._tdet_register.kTDET_Control (*C enumerator*), 926
drivers_MCX_MCXA_MCXA366._tdet_register.kTDET_GlitchFilter0 (*C enumerator*), 926
drivers_MCX_MCXA_MCXA366._tdet_register.kTDET_GlitchFilter1 (*C enumerator*), 926
drivers_MCX_MCXA_MCXA366._tdet_register.kTDET_InterruptEnable (*C enumerator*), 926

drivers_MCX_MCXA_MCXA366._tdet_register.kTDET_Lock (*C enumerator*), 926
drivers_MCX_MCXA_MCXA366._tdet_register.kTDET_NoRegister (*C enumerator*), 926
drivers_MCX_MCXA_MCXA366._tdet_register.kTDET_PinConfigurationRegisters (*C enumerator*), 926
drivers_MCX_MCXA_MCXA366._tdet_register.kTDET_PinPolarity (*C enumerator*), 926
drivers_MCX_MCXA_MCXA366._tdet_register.kTDET_Status (*C enumerator*), 926
drivers_MCX_MCXA_MCXA366._tdet_register.kTDET_TamperEnable (*C enumerator*), 926
drivers_MCX_MCXA_MCXA366._tdet_register.kTDET_TamperSeconds (*C enumerator*), 926
drivers_MCX_MCXA_MCXA366._tdet_status_flag (*C enum*), 924
drivers_MCX_MCXA_MCXA366._tdet_status_flag.kTDET_StatusAll (*C enumerator*), 924
drivers_MCX_MCXA_MCXA366._tdet_status_flag.kTDET_StatusTamperAcknowledgeFlag (*C enumerator*), 924
drivers_MCX_MCXA_MCXA366._tdet_status_flag.kTDET_StatusTamperFlag (*C enumerator*), 924
drivers_MCX_MCXA_MCXA366._tdet_status_flag.kTDET_StatusTamperPinTamper0 (*C enumerator*), 924
drivers_MCX_MCXA_MCXA366._tdet_status_flag.kTDET_StatusTamperPinTamper1 (*C enumerator*), 924
drivers_MCX_MCXA_MCXA366._tdet_status_flag.kTDET_TIF0 (*C enumerator*), 924
drivers_MCX_MCXA_MCXA366._tdet_tamper (*C enum*), 925
drivers_MCX_MCXA_MCXA366._tdet_tamper.kTDET_TamperAll (*C enumerator*), 925
drivers_MCX_MCXA_MCXA366._tdet_tamper.kTDET_TamperTamperPin0 (*C enumerator*), 925
drivers_MCX_MCXA_MCXA366._tdet_tamper.kTDET_TamperTamperPin1 (*C enumerator*), 925
drivers_MCX_MCXA_MCXA366._tdet_tamper.kTDET_TamperTamperPinAll (*C enumerator*), 925
drivers_MCX_MCXA_MCXA366._tdet_tamper.kTDET_TamperTIF0 (*C enumerator*), 925
drivers_MCX_MCXA_MCXA366._tdet_update_mode (*C enum*), 921
drivers_MCX_MCXA_MCXA366._tdet_update_mode.kTDET_StatusLockNormal (*C enumerator*), 921
drivers_MCX_MCXA_MCXA366._tdet_update_mode.kTDET_StatusLockWithTamper (*C enumerator*), 921
drivers_MCX_MCXA_MCXA366._trdc_controller (*C enum*), 940
drivers_MCX_MCXA_MCXA366._trdc_controller.kTRDC_MemBlockController0 (*C enumerator*), 941
drivers_MCX_MCXA_MCXA366._trdc_controller.kTRDC_MemBlockController1 (*C enumerator*), 941
drivers_MCX_MCXA_MCXA366._trdc_controller.kTRDC_MemBlockController2 (*C enumerator*), 941
drivers_MCX_MCXA_MCXA366._trdc_controller.kTRDC_MemBlockController3 (*C enumerator*), 941
drivers_MCX_MCXA_MCXA366._trdc_controller.kTRDC_MemRegionChecker0 (*C enumerator*), 941
drivers_MCX_MCXA_MCXA366._trdc_controller.kTRDC_MemRegionChecker1 (*C enumerator*), 941
drivers_MCX_MCXA_MCXA366._trdc_controller.kTRDC_MemRegionChecker2 (*C enumerator*), 941
drivers_MCX_MCXA_MCXA366._trdc_controller.kTRDC_MemRegionChecker3 (*C enumerator*), 941
drivers_MCX_MCXA_MCXA366._trdc_controller.kTRDC_MemRegionChecker4 (*C enumerator*), 941
drivers_MCX_MCXA_MCXA366._trdc_controller.kTRDC_MemRegionChecker5 (*C enumerator*), 941
drivers_MCX_MCXA_MCXA366._trdc_controller.kTRDC_MemRegionChecker6 (*C enumerator*), 941
drivers_MCX_MCXA_MCXA366._trdc_did_sel (*C enum*), 939
drivers_MCX_MCXA_MCXA366._trdc_did_sel.kTRDC_DidInput (*C enumerator*), 939
drivers_MCX_MCXA_MCXA366._trdc_did_sel.kTRDC_DidMda (*C enumerator*), 939
drivers_MCX_MCXA_MCXA366._trdc_did_sel.kTRDC_DidMdaAndInput (*C enumerator*), 939

drivers_MCX_MCXA_MCXA366._trdc_did_sel.kTRDC_DidReserved (*C enumerator*), 939
drivers_MCX_MCXA_MCXA366._trdc_domain_error (*C struct*), 952
drivers_MCX_MCXA_MCXA366._trdc_domain_error.address (*C var*), 952
drivers_MCX_MCXA_MCXA366._trdc_domain_error.controller (*C var*), 952
drivers_MCX_MCXA_MCXA366._trdc_domain_error.domainId (*C var*), 953
drivers_MCX_MCXA_MCXA366._trdc_domain_error.errorAttr (*C var*), 953
drivers_MCX_MCXA_MCXA366._trdc_domain_error.errorPort (*C var*), 953
drivers_MCX_MCXA_MCXA366._trdc_domain_error.errorState (*C var*), 952
drivers_MCX_MCXA_MCXA366._trdc_domain_error.errorType (*C var*), 953
drivers_MCX_MCXA_MCXA366._trdc_domain_error.slaveMemoryIdx (*C var*), 953
drivers_MCX_MCXA_MCXA366._TRDC_DomainAssignment_Type (*C struct*), 958
drivers_MCX_MCXA_MCXA366._TRDC_DomainAssignment_Type.___unnamed79___ (*C union*), 971
drivers_MCX_MCXA_MCXA366._TRDC_DomainAssignment_Type.___unnamed79___.MDA_DFMT0 (*C struct*), 972
drivers_MCX_MCXA_MCXA366._TRDC_DomainAssignment_Type.___unnamed79___.MDA_DFMT0 (*C var*), 972
drivers_MCX_MCXA_MCXA366._TRDC_DomainAssignment_Type.___unnamed79___.MDA_DFMT1 (*C struct*), 972
drivers_MCX_MCXA_MCXA366._TRDC_DomainAssignment_Type.___unnamed79___.MDA_DFMT1 (*C var*), 972
drivers_MCX_MCXA_MCXA366._TRDC_DomainError_Type (*C struct*), 957
drivers_MCX_MCXA_MCXA366._TRDC_DomainError_Type.MBC_DERR (*C struct*), 971
drivers_MCX_MCXA_MCXA366._TRDC_DomainError_Type.MRC_DERR (*C struct*), 971
drivers_MCX_MCXA_MCXA366._trdc_error_attr (*C enum*), 942
drivers_MCX_MCXA_MCXA366._trdc_error_attr.kTRDC_ErrorNonSecurePrivilegeData (*C enumerator*), 942
drivers_MCX_MCXA_MCXA366._trdc_error_attr.kTRDC_ErrorNonSecurePrivilegeInst (*C enumerator*), 942
drivers_MCX_MCXA_MCXA366._trdc_error_attr.kTRDC_ErrorNonSecureUserData (*C enumerator*), 942
drivers_MCX_MCXA_MCXA366._trdc_error_attr.kTRDC_ErrorNonSecureUserInst (*C enumerator*), 942
drivers_MCX_MCXA_MCXA366._trdc_error_attr.kTRDC_ErrorSecurePrivilegeData (*C enumerator*), 942
drivers_MCX_MCXA_MCXA366._trdc_error_attr.kTRDC_ErrorSecurePrivilegeInst (*C enumerator*), 942
drivers_MCX_MCXA_MCXA366._trdc_error_attr.kTRDC_ErrorSecureUserData (*C enumerator*), 942
drivers_MCX_MCXA_MCXA366._trdc_error_attr.kTRDC_ErrorSecureUserInst (*C enumerator*), 942
drivers_MCX_MCXA_MCXA366._trdc_error_state (*C enum*), 941
drivers_MCX_MCXA_MCXA366._trdc_error_state.kTRDC_ErrorStateMulti (*C enumerator*), 941
drivers_MCX_MCXA_MCXA366._trdc_error_state.kTRDC_ErrorStateNone (*C enumerator*), 941
drivers_MCX_MCXA_MCXA366._trdc_error_state.kTRDC_ErrorStateNone1 (*C enumerator*), 941
drivers_MCX_MCXA_MCXA366._trdc_error_state.kTRDC_ErrorStateSingle (*C enumerator*), 941
drivers_MCX_MCXA_MCXA366._trdc_error_type (*C enum*), 942
drivers_MCX_MCXA_MCXA366._trdc_error_type.kTRDC_ErrorTypeRead (*C enumerator*), 942
drivers_MCX_MCXA_MCXA366._trdc_error_type.kTRDC_ErrorTypeWrite (*C enumerator*), 942
drivers_MCX_MCXA_MCXA366._trdc_flw_config (*C struct*), 952
drivers_MCX_MCXA_MCXA366._trdc_flw_config.arrayBaseAddr (*C var*), 952
drivers_MCX_MCXA_MCXA366._trdc_flw_config.blockCount (*C var*), 952
drivers_MCX_MCXA_MCXA366._trdc_flw_config.enable (*C var*), 952
drivers_MCX_MCXA_MCXA366._trdc_flw_config.lock (*C var*), 952
drivers_MCX_MCXA_MCXA366._TRDC_FLW_Type (*C struct*), 957
drivers_MCX_MCXA_MCXA366._TRDC_General_Type (*C struct*), 956
drivers_MCX_MCXA_MCXA366._trdc_hardware_config (*C struct*), 949
drivers_MCX_MCXA_MCXA366._trdc_hardware_config.domainNumber (*C var*), 949

drivers_MCX_MCXA_MCXA366._trdc_hardware_config.masterNumber (*C var*), 949
drivers_MCX_MCXA_MCXA366._trdc_hardware_config.mbcNumber (*C var*), 949
drivers_MCX_MCXA_MCXA366._trdc_hardware_config.mrcNumber (*C var*), 949
drivers_MCX_MCXA_MCXA366._trdc_idau_config (*C struct*), 951
drivers_MCX_MCXA_MCXA366._trdc_idau_config.___pad0___ (*C var*), 951
drivers_MCX_MCXA_MCXA366._trdc_idau_config.___pad1___ (*C var*), 952
drivers_MCX_MCXA_MCXA366._trdc_idau_config.lockNonsecureMPU (*C var*), 952
drivers_MCX_MCXA_MCXA366._trdc_idau_config.lockNonsecureVTOR (*C var*), 952
drivers_MCX_MCXA_MCXA366._trdc_idau_config.lockSAU (*C var*), 952
drivers_MCX_MCXA_MCXA366._trdc_idau_config.lockSecureMPU (*C var*), 952
drivers_MCX_MCXA_MCXA366._trdc_idau_config.lockSecureVTOR (*C var*), 951
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit (*C enum*), 945
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit0 (*C enumerator*), 946
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit1 (*C enumerator*), 946
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit2 (*C enumerator*), 946
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit3 (*C enumerator*), 946
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit4 (*C enumerator*), 946
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit5 (*C enumerator*), 946
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit6 (*C enumerator*), 946
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit7 (*C enumerator*), 946
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit8 (*C enumerator*), 946
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit9 (*C enumerator*), 946
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit10 (*C enumerator*), 946
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit11 (*C enumerator*), 946
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit12 (*C enumerator*), 946
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit13 (*C enumerator*), 946
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit14 (*C enumerator*), 946
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit15 (*C enumerator*), 946
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit16 (*C enumerator*), 947
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit17 (*C enumerator*), 947
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit18 (*C enumerator*), 947
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit19 (*C enumerator*), 947
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit20 (*C enumerator*), 947
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit21 (*C enumerator*), 947
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit22 (*C enumerator*), 947
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit23 (*C enumerator*), 947
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit24 (*C enumerator*), 947
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit25 (*C enumerator*), 947
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit26 (*C enumerator*), 947
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit27 (*C enumerator*), 947
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit28 (*C enumerator*), 947
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit29 (*C enumerator*), 947
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit30 (*C enumerator*), 947
drivers_MCX_MCXA_MCXA366._trdc_MBC_bit.kTRDC_MbcBit31 (*C enumerator*), 947
drivers_MCX_MCXA_MCXA366._trdc_MBC_domain (*C enum*), 945
drivers_MCX_MCXA_MCXA366._trdc_MBC_domain.kTRDC_MbcDomain0 (*C enumerator*), 945
drivers_MCX_MCXA_MCXA366._trdc_MBC_domain.kTRDC_MbcDomain1 (*C enumerator*), 945
drivers_MCX_MCXA_MCXA366._trdc_MBC_domain.kTRDC_MbcDomain2 (*C enumerator*), 945
drivers_MCX_MCXA_MCXA366._trdc_MBC_domain.kTRDC_MbcDomain3 (*C enumerator*), 945
drivers_MCX_MCXA_MCXA366._trdc_MBC_domain.kTRDC_MbcDomain4 (*C enumerator*), 945
drivers_MCX_MCXA_MCXA366._trdc_MBC_domain.kTRDC_MbcDomain5 (*C enumerator*), 945
drivers_MCX_MCXA_MCXA366._trdc_MBC_domain.kTRDC_MbcDomain6 (*C enumerator*), 945
drivers_MCX_MCXA_MCXA366._trdc_MBC_domain.kTRDC_MbcDomain7 (*C enumerator*), 945
drivers_MCX_MCXA_MCXA366._trdc_MBC_memory (*C enum*), 945
drivers_MCX_MCXA_MCXA366._trdc_mbc_memory_block_config (*C struct*), 955
drivers_MCX_MCXA_MCXA366._trdc_mbc_memory_block_config.domainIdx (*C var*), 956
drivers_MCX_MCXA_MCXA366._trdc_mbc_memory_block_config.mbcIdx (*C var*), 956

drivers_MCX_MCXA_MCXA366._trdc_mbc_memory_block_config.memoryAccessControlSelect (*C var*), 955
drivers_MCX_MCXA_MCXA366._trdc_mbc_memory_block_config.memoryBlockIdx (*C var*), 956
drivers_MCX_MCXA_MCXA366._trdc_mbc_memory_block_config.nseEnable (*C var*), 955
drivers_MCX_MCXA_MCXA366._trdc_mbc_memory_block_config.slaveMemoryIdx (*C var*), 956
drivers_MCX_MCXA_MCXA366._trdc_MBC_memory.kTRDC_MbcSlaveMemory0 (*C enumerator*), 945
drivers_MCX_MCXA_MCXA366._trdc_MBC_memory.kTRDC_MbcSlaveMemory1 (*C enumerator*), 945
drivers_MCX_MCXA_MCXA366._trdc_MBC_memory.kTRDC_MbcSlaveMemory2 (*C enumerator*), 945
drivers_MCX_MCXA_MCXA366._trdc_MBC_memory.kTRDC_MbcSlaveMemory3 (*C enumerator*), 945
drivers_MCX_MCXA_MCXA366._trdc_mbc_nse_update_config (*C struct*), 955
drivers_MCX_MCXA_MCXA366._trdc_mbc_nse_update_config.___pad0___ (*C var*), 955
drivers_MCX_MCXA_MCXA366._trdc_mbc_nse_update_config.___pad1___ (*C var*), 955
drivers_MCX_MCXA_MCXA366._trdc_mbc_nse_update_config.___pad2___ (*C var*), 955
drivers_MCX_MCXA_MCXA366._trdc_mbc_nse_update_config.___pad3___ (*C var*), 955
drivers_MCX_MCXA_MCXA366._trdc_mbc_nse_update_config.autoIncrement (*C var*), 955
drivers_MCX_MCXA_MCXA366._trdc_mbc_nse_update_config.domianSelect (*C var*), 955
drivers_MCX_MCXA_MCXA366._trdc_mbc_nse_update_config.memorySelect (*C var*), 955
drivers_MCX_MCXA_MCXA366._trdc_mbc_nse_update_config.wordIdx (*C var*), 955
drivers_MCX_MCXA_MCXA366._TRDC_MBC_Type (*C struct*), 958
drivers_MCX_MCXA_MCXA366._trdc_memory_access_control_config (*C struct*), 953
drivers_MCX_MCXA_MCXA366._trdc_memory_access_control_config.___pad0___ (*C var*), 953
drivers_MCX_MCXA_MCXA366._trdc_memory_access_control_config.___pad1___ (*C var*), 953
drivers_MCX_MCXA_MCXA366._trdc_memory_access_control_config.___pad2___ (*C var*), 954
drivers_MCX_MCXA_MCXA366._trdc_memory_access_control_config.___pad3___ (*C var*), 954
drivers_MCX_MCXA_MCXA366._trdc_memory_access_control_config.lock (*C var*), 954
drivers_MCX_MCXA_MCXA366._trdc_memory_access_control_config.nonsecurePrivR (*C var*), 953
drivers_MCX_MCXA_MCXA366._trdc_memory_access_control_config.nonsecurePrivW (*C var*), 953
drivers_MCX_MCXA_MCXA366._trdc_memory_access_control_config.nonsecurePrivX (*C var*), 953
drivers_MCX_MCXA_MCXA366._trdc_memory_access_control_config.nonsecureUsrR (*C var*), 953
drivers_MCX_MCXA_MCXA366._trdc_memory_access_control_config.nonsecureUsrW (*C var*), 953
drivers_MCX_MCXA_MCXA366._trdc_memory_access_control_config.nonsecureUsrX (*C var*), 953
drivers_MCX_MCXA_MCXA366._trdc_memory_access_control_config.securePrivR (*C var*), 954
drivers_MCX_MCXA_MCXA366._trdc_memory_access_control_config.securePrivW (*C var*), 954
drivers_MCX_MCXA_MCXA366._trdc_memory_access_control_config.securePrivX (*C var*), 954
drivers_MCX_MCXA_MCXA366._trdc_memory_access_control_config.secureUsrR (*C var*), 954
drivers_MCX_MCXA_MCXA366._trdc_memory_access_control_config.secureUsrW (*C var*), 954
drivers_MCX_MCXA_MCXA366._trdc_memory_access_control_config.secureUsrX (*C var*), 953
drivers_MCX_MCXA_MCXA366._trdc_MRC_domain (*C enum*), 943
drivers_MCX_MCXA_MCXA366._trdc_MRC_domain.kTRDC_MrcDomain0 (*C enumerator*), 944
drivers_MCX_MCXA_MCXA366._trdc_MRC_domain.kTRDC_MrcDomain1 (*C enumerator*), 944
drivers_MCX_MCXA_MCXA366._trdc_MRC_domain.kTRDC_MrcDomain2 (*C enumerator*), 944
drivers_MCX_MCXA_MCXA366._trdc_MRC_domain.kTRDC_MrcDomain3 (*C enumerator*), 944
drivers_MCX_MCXA_MCXA366._trdc_MRC_domain.kTRDC_MrcDomain4 (*C enumerator*), 944
drivers_MCX_MCXA_MCXA366._trdc_MRC_domain.kTRDC_MrcDomain5 (*C enumerator*), 944
drivers_MCX_MCXA_MCXA366._trdc_MRC_domain.kTRDC_MrcDomain6 (*C enumerator*), 944
drivers_MCX_MCXA_MCXA366._trdc_MRC_domain.kTRDC_MrcDomain7 (*C enumerator*), 944
drivers_MCX_MCXA_MCXA366._trdc_MRC_domain.kTRDC_MrcDomain8 (*C enumerator*), 944
drivers_MCX_MCXA_MCXA366._trdc_MRC_domain.kTRDC_MrcDomain9 (*C enumerator*), 944
drivers_MCX_MCXA_MCXA366._trdc_MRC_domain.kTRDC_MrcDomain10 (*C enumerator*), 944
drivers_MCX_MCXA_MCXA366._trdc_MRC_domain.kTRDC_MrcDomain11 (*C enumerator*), 944

drivers_MCX_MCXA_MCXA366._trdc_MRC_domain.kTRDC_MrcDomain12 (*C enumerator*), 944
drivers_MCX_MCXA_MCXA366._trdc_MRC_domain.kTRDC_MrcDomain13 (*C enumerator*), 944
drivers_MCX_MCXA_MCXA366._trdc_MRC_domain.kTRDC_MrcDomain14 (*C enumerator*), 944
drivers_MCX_MCXA_MCXA366._trdc_MRC_domain.kTRDC_MrcDomain15 (*C enumerator*), 944
drivers_MCX_MCXA_MCXA366._trdc_mrc_region_descriptor_config (*C struct*), 954
drivers_MCX_MCXA_MCXA366._trdc_mrc_region_descriptor_config.domainIdx (*C var*), 955
drivers_MCX_MCXA_MCXA366._trdc_mrc_region_descriptor_config.endAddr (*C var*), 954
drivers_MCX_MCXA_MCXA366._trdc_mrc_region_descriptor_config.memoryAccessControlSelect (*C var*), 954
drivers_MCX_MCXA_MCXA366._trdc_mrc_region_descriptor_config.mrcIdx (*C var*), 954
drivers_MCX_MCXA_MCXA366._trdc_mrc_region_descriptor_config.nseEnable (*C var*), 954
drivers_MCX_MCXA_MCXA366._trdc_mrc_region_descriptor_config.regionIdx (*C var*), 955
drivers_MCX_MCXA_MCXA366._trdc_mrc_region_descriptor_config.startAddr (*C var*), 954
drivers_MCX_MCXA_MCXA366._trdc_mrc_region_descriptor_config.valid (*C var*), 954
drivers_MCX_MCXA_MCXA366._TRDC_MRC_Type (*C struct*), 968
drivers_MCX_MCXA_MCXA366._trdc_non_processor_domain_assignment (*C struct*), 950
drivers_MCX_MCXA_MCXA366._trdc_non_processor_domain_assignment.___pad0___ (*C var*), 951
drivers_MCX_MCXA_MCXA366._trdc_non_processor_domain_assignment.___pad1___ (*C var*), 951
drivers_MCX_MCXA_MCXA366._trdc_non_processor_domain_assignment.bypassDomainId (*C var*), 951
drivers_MCX_MCXA_MCXA366._trdc_non_processor_domain_assignment.domainId (*C var*), 950
drivers_MCX_MCXA_MCXA366._trdc_non_processor_domain_assignment.lock (*C var*), 951
drivers_MCX_MCXA_MCXA366._trdc_non_processor_domain_assignment.privilegeAttr (*C var*), 951
drivers_MCX_MCXA_MCXA366._trdc_non_processor_domain_assignment.secureAttr (*C var*), 951
drivers_MCX_MCXA_MCXA366._trdc_pid_config (*C struct*), 951
drivers_MCX_MCXA_MCXA366._trdc_pid_config.___pad0___ (*C var*), 951
drivers_MCX_MCXA_MCXA366._trdc_pid_config.___pad1___ (*C var*), 951
drivers_MCX_MCXA_MCXA366._trdc_pid_config.lock (*C var*), 951
drivers_MCX_MCXA_MCXA366._trdc_pid_config.pid (*C var*), 951
drivers_MCX_MCXA_MCXA366._trdc_pid_domain_hit_config (*C enum*), 939
drivers_MCX_MCXA_MCXA366._trdc_pid_domain_hit_config.kTRDC_pidDomainHitExclusive (*C enumerator*), 940
drivers_MCX_MCXA_MCXA366._trdc_pid_domain_hit_config.kTRDC_pidDomainHitInclusive (*C enumerator*), 940
drivers_MCX_MCXA_MCXA366._trdc_pid_domain_hit_config.kTRDC_pidDomainHitNone0 (*C enumerator*), 939
drivers_MCX_MCXA_MCXA366._trdc_pid_domain_hit_config.kTRDC_pidDomainHitNone1 (*C enumerator*), 940
drivers_MCX_MCXA_MCXA366._trdc_pid_lock (*C enum*), 940
drivers_MCX_MCXA_MCXA366._trdc_pid_lock.kTRDC_PidLocked (*C enumerator*), 940
drivers_MCX_MCXA_MCXA366._trdc_pid_lock.kTRDC_PidUnlocked0 (*C enumerator*), 940
drivers_MCX_MCXA_MCXA366._trdc_pid_lock.kTRDC_PidUnlocked1 (*C enumerator*), 940
drivers_MCX_MCXA_MCXA366._trdc_pid_lock.kTRDC_PidUnlocked2 (*C enumerator*), 940
drivers_MCX_MCXA_MCXA366._trdc_privilege_attr (*C enum*), 940
drivers_MCX_MCXA_MCXA366._trdc_privilege_attr.kTRDC_ForcePrivilege (*C enumerator*), 940
drivers_MCX_MCXA_MCXA366._trdc_privilege_attr.kTRDC_ForceUser (*C enumerator*), 940
drivers_MCX_MCXA_MCXA366._trdc_privilege_attr.kTRDC_MasterPrivilege (*C enumerator*), 940
drivers_MCX_MCXA_MCXA366._trdc_privilege_attr.kTRDC_MasterPrivilege1 (*C enumerator*), 940
drivers_MCX_MCXA_MCXA366._trdc_processor_domain_assignment (*C struct*), 950
drivers_MCX_MCXA_MCXA366._trdc_processor_domain_assignment.___pad0___ (*C var*), 950
drivers_MCX_MCXA_MCXA366._trdc_processor_domain_assignment.___pad1___ (*C var*), 950
drivers_MCX_MCXA_MCXA366._trdc_processor_domain_assignment.domainId (*C var*), 950
drivers_MCX_MCXA_MCXA366._trdc_processor_domain_assignment.domainIdSelect (*C var*), 950

drivers_MCX_MCXA_MCXA366._trdc_processor_domain_assignment.lock (*C var*), 950
drivers_MCX_MCXA_MCXA366._trdc_processor_domain_assignment.pid (*C var*), 950
drivers_MCX_MCXA_MCXA366._trdc_processor_domain_assignment.pidDomainHitConfig (*C var*), 950
drivers_MCX_MCXA_MCXA366._trdc_processor_domain_assignment.pidMask (*C var*), 950
drivers_MCX_MCXA_MCXA366._trdc_processor_domain_assignment.secureAttr (*C var*), 950
drivers_MCX_MCXA_MCXA366._trdc_region_descriptor (*C enum*), 942
drivers_MCX_MCXA_MCXA366._trdc_region_descriptor.kTRDC_RegionDescriptor0 (*C enumerator*), 942
drivers_MCX_MCXA_MCXA366._trdc_region_descriptor.kTRDC_RegionDescriptor1 (*C enumerator*), 943
drivers_MCX_MCXA_MCXA366._trdc_region_descriptor.kTRDC_RegionDescriptor2 (*C enumerator*), 943
drivers_MCX_MCXA_MCXA366._trdc_region_descriptor.kTRDC_RegionDescriptor3 (*C enumerator*), 943
drivers_MCX_MCXA_MCXA366._trdc_region_descriptor.kTRDC_RegionDescriptor4 (*C enumerator*), 943
drivers_MCX_MCXA_MCXA366._trdc_region_descriptor.kTRDC_RegionDescriptor5 (*C enumerator*), 943
drivers_MCX_MCXA_MCXA366._trdc_region_descriptor.kTRDC_RegionDescriptor6 (*C enumerator*), 943
drivers_MCX_MCXA_MCXA366._trdc_region_descriptor.kTRDC_RegionDescriptor7 (*C enumerator*), 943
drivers_MCX_MCXA_MCXA366._trdc_region_descriptor.kTRDC_RegionDescriptor8 (*C enumerator*), 943
drivers_MCX_MCXA_MCXA366._trdc_region_descriptor.kTRDC_RegionDescriptor9 (*C enumerator*), 943
drivers_MCX_MCXA_MCXA366._trdc_region_descriptor.kTRDC_RegionDescriptor10 (*C enumerator*), 943
drivers_MCX_MCXA_MCXA366._trdc_region_descriptor.kTRDC_RegionDescriptor11 (*C enumerator*), 943
drivers_MCX_MCXA_MCXA366._trdc_region_descriptor.kTRDC_RegionDescriptor12 (*C enumerator*), 943
drivers_MCX_MCXA_MCXA366._trdc_region_descriptor.kTRDC_RegionDescriptor13 (*C enumerator*), 943
drivers_MCX_MCXA_MCXA366._trdc_region_descriptor.kTRDC_RegionDescriptor14 (*C enumerator*), 943
drivers_MCX_MCXA_MCXA366._trdc_region_descriptor.kTRDC_RegionDescriptor15 (*C enumerator*), 943
drivers_MCX_MCXA_MCXA366._trdc_secure_attr (*C enum*), 939
drivers_MCX_MCXA_MCXA366._trdc_secure_attr.kTRDC_ForceNonSecure (*C enumerator*), 939
drivers_MCX_MCXA_MCXA366._trdc_secure_attr.kTRDC_ForceSecure (*C enumerator*), 939
drivers_MCX_MCXA_MCXA366._trdc_secure_attr.kTRDC_MasterSecure (*C enumerator*), 939
drivers_MCX_MCXA_MCXA366._trdc_secure_attr.kTRDC_MasterSecure1 (*C enumerator*), 939
drivers_MCX_MCXA_MCXA366._trdc_slave_memory_hardware_config (*C struct*), 949
drivers_MCX_MCXA_MCXA366._trdc_slave_memory_hardware_config.blockNum (*C var*), 950
drivers_MCX_MCXA_MCXA366._trdc_slave_memory_hardware_config.blockSize (*C var*), 950
drivers_MCX_MCXA_MCXA366._trng_clock_mode (*C enum*), 974
drivers_MCX_MCXA_MCXA366._trng_clock_mode.kTRNG_ClockModeRingOscillator (*C enumerator*), 974
drivers_MCX_MCXA_MCXA366._trng_clock_mode.kTRNG_ClockModeSystem (*C enumerator*), 974
drivers_MCX_MCXA_MCXA366._trng_ring_osc_div (*C enum*), 974
drivers_MCX_MCXA_MCXA366._trng_ring_osc_div.kTRNG_RingOscDiv0 (*C enumerator*), 974
drivers_MCX_MCXA_MCXA366._trng_ring_osc_div.kTRNG_RingOscDiv2 (*C enumerator*), 974
drivers_MCX_MCXA_MCXA366._trng_ring_osc_div.kTRNG_RingOscDiv4 (*C enumerator*), 974
drivers_MCX_MCXA_MCXA366._trng_ring_osc_div.kTRNG_RingOscDiv8 (*C enumerator*), 974
drivers_MCX_MCXA_MCXA366._trng_sample_mode (*C enum*), 974

drivers_MCX_MCXA_MCXA366._trng_sample_mode.kTRNG_SampleModeRaw (*C enumerator*), 974
drivers_MCX_MCXA_MCXA366._trng_sample_mode.kTRNG_SampleModeVonNeumann (*C enumerator*), 974
drivers_MCX_MCXA_MCXA366._trng_sample_mode.kTRNG_SampleModeVonNeumannRaw (*C enumerator*), 974
drivers_MCX_MCXA_MCXA366._trng_statistical_check_limit (*C struct*), 976
drivers_MCX_MCXA_MCXA366._trng_statistical_check_limit.maximum (*C var*), 976
drivers_MCX_MCXA_MCXA366._trng_statistical_check_limit.minimum (*C var*), 976
drivers_MCX_MCXA_MCXA366._trng_user_config (*C struct*), 976
drivers_MCX_MCXA_MCXA366._trng_user_config.clockMode (*C var*), 976
drivers_MCX_MCXA_MCXA366._trng_user_config.entropyDelay (*C var*), 977
drivers_MCX_MCXA_MCXA366._trng_user_config.frequencyCountLimit (*C var*), 978
drivers_MCX_MCXA_MCXA366._trng_user_config.lock (*C var*), 976
drivers_MCX_MCXA_MCXA366._trng_user_config.longRunMaxLimit (*C var*), 977
drivers_MCX_MCXA_MCXA366._trng_user_config.monobitLimit (*C var*), 977
drivers_MCX_MCXA_MCXA366._trng_user_config.oscillatorMode (*C var*), 977
drivers_MCX_MCXA_MCXA366._trng_user_config.pokerLimit (*C var*), 978
drivers_MCX_MCXA_MCXA366._trng_user_config.retryCount (*C var*), 977
drivers_MCX_MCXA_MCXA366._trng_user_config.ringOsc2Div (*C var*), 977
drivers_MCX_MCXA_MCXA366._trng_user_config.ringOscDiv (*C var*), 976
drivers_MCX_MCXA_MCXA366._trng_user_config.runBit1Limit (*C var*), 977
drivers_MCX_MCXA_MCXA366._trng_user_config.runBit2Limit (*C var*), 977
drivers_MCX_MCXA_MCXA366._trng_user_config.runBit3Limit (*C var*), 977
drivers_MCX_MCXA_MCXA366._trng_user_config.runBit4Limit (*C var*), 977
drivers_MCX_MCXA_MCXA366._trng_user_config.runBit5Limit (*C var*), 977
drivers_MCX_MCXA_MCXA366._trng_user_config.runBit6PlusLimit (*C var*), 978
drivers_MCX_MCXA_MCXA366._trng_user_config.sampleMode (*C var*), 976
drivers_MCX_MCXA_MCXA366._trng_user_config.sampleSize (*C var*), 977
drivers_MCX_MCXA_MCXA366._trng_user_config.sparseBitLimit (*C var*), 977
drivers_MCX_MCXA_MCXA366._utick_mode (*C enum*), 979
drivers_MCX_MCXA_MCXA366._utick_mode.kUTICK_Onetime (*C enumerator*), 979
drivers_MCX_MCXA_MCXA366._utick_mode.kUTICK_Repeat (*C enumerator*), 979
drivers_MCX_MCXA_MCXA366._vbat_bandgap_refresh_period (*C enum*), 828
drivers_MCX_MCXA_MCXA366._vbat_bandgap_refresh_period.kVBAT_BandgapRefresh7P8125ms (*C enumerator*), 828
drivers_MCX_MCXA_MCXA366._vbat_bandgap_refresh_period.kVBAT_BandgapRefresh15P625ms (*C enumerator*), 828
drivers_MCX_MCXA_MCXA366._vbat_bandgap_refresh_period.kVBAT_BandgapRefresh31P25ms (*C enumerator*), 828
drivers_MCX_MCXA_MCXA366._vbat_bandgap_refresh_period.kVBAT_BandgapRefresh62P5ms (*C enumerator*), 828
drivers_MCX_MCXA_MCXA366._vbat_bandgap_timer0_timeout_period (*C enum*), 828
drivers_MCX_MCXA_MCXA366._vbat_bandgap_timer0_timeout_period.kVBAT_BangapTimer0Timeout1s (*C enumerator*), 828
drivers_MCX_MCXA_MCXA366._vbat_bandgap_timer0_timeout_period.kVBAT_BangapTimer0Timeout31P25ms (*C enumerator*), 828
drivers_MCX_MCXA_MCXA366._vbat_bandgap_timer0_timeout_period.kVBAT_BangapTimer0Timeout62P5ms (*C enumerator*), 828
drivers_MCX_MCXA_MCXA366._vbat_bandgap_timer0_timeout_period.kVBAT_BangapTimer0Timeout125ms (*C enumerator*), 828
drivers_MCX_MCXA_MCXA366._vbat_bandgap_timer0_timeout_period.kVBAT_BangapTimer0Timeout250ms (*C enumerator*), 828
drivers_MCX_MCXA_MCXA366._vbat_bandgap_timer0_timeout_period.kVBAT_BangapTimer0Timeout500ms (*C enumerator*), 828
drivers_MCX_MCXA_MCXA366._vbat_bandgap_timer_id (*C enum*), 827
drivers_MCX_MCXA_MCXA366._vbat_bandgap_timer_id.kVBAT_BandgapTimer0 (*C enumerator*), 827

drivers_MCX_MCXA_MCXA366._vbat_bandgap_timer_id.kVBAT_BandgapTimer1 (*C enumerator*), 827
drivers_MCX_MCXA_MCXA366._vbat_clock_enable (*C enum*), 827
drivers_MCX_MCXA_MCXA366._vbat_clock_enable.kVBAT_EnableClockToDomain0 (*C enumerator*), 827
drivers_MCX_MCXA_MCXA366._vbat_clock_enable.kVBAT_EnableClockToDomain1 (*C enumerator*), 827
drivers_MCX_MCXA_MCXA366._vbat_clock_enable.kVBAT_EnableClockToDomain2 (*C enumerator*), 827
drivers_MCX_MCXA_MCXA366._vbat_clock_enable.kVBAT_EnableClockToDomain3 (*C enumerator*), 827
drivers_MCX_MCXA_MCXA366._vbat_clock_monitor_config (*C struct*), 845
drivers_MCX_MCXA_MCXA366._vbat_clock_monitor_config.freqTrim (*C var*), 845
drivers_MCX_MCXA_MCXA366._vbat_clock_monitor_config.lock (*C var*), 845
drivers_MCX_MCXA_MCXA366._vbat_clock_monitor_divide_trim (*C enum*), 831
drivers_MCX_MCXA_MCXA366._vbat_clock_monitor_divide_trim.kVBAT_ClockMonitorOperateAt1kHz (*C enumerator*), 831
drivers_MCX_MCXA_MCXA366._vbat_clock_monitor_divide_trim.kVBAT_ClockMonitorOperateAt64Hz (*C enumerator*), 831
drivers_MCX_MCXA_MCXA366._vbat_clock_monitor_freq_trim (*C enum*), 831
drivers_MCX_MCXA_MCXA366._vbat_clock_monitor_freq_trim.kVBAT_ClockMonitorAssert2Cycle (*C enumerator*), 831
drivers_MCX_MCXA_MCXA366._vbat_clock_monitor_freq_trim.kVBAT_ClockMonitorAssert4Cycle (*C enumerator*), 831
drivers_MCX_MCXA_MCXA366._vbat_clock_monitor_freq_trim.kVBAT_ClockMonitorAssert6Cycle (*C enumerator*), 831
drivers_MCX_MCXA_MCXA366._vbat_clock_monitor_freq_trim.kVBAT_ClockMonitorAssert8Cycle (*C enumerator*), 831
drivers_MCX_MCXA_MCXA366._vbat_fro16k_config (*C struct*), 845
drivers_MCX_MCXA_MCXA366._vbat_fro16k_config.enabledConnectionsMask (*C var*), 845
drivers_MCX_MCXA_MCXA366._vbat_fro16k_config.enableFRO16k (*C var*), 845
drivers_MCX_MCXA_MCXA366._vbat_internal_module_supply (*C enum*), 831
drivers_MCX_MCXA_MCXA366._vbat_internal_module_supply.kVBAT_ModuleSuppliedByVddBat (*C enumerator*), 831
drivers_MCX_MCXA_MCXA366._vbat_internal_module_supply.kVBAT_ModuleSuppliedByVddSys (*C enumerator*), 831
drivers_MCX_MCXA_MCXA366._vbat_interrupt_enable (*C enum*), 825
drivers_MCX_MCXA_MCXA366._vbat_interrupt_enable.kVBAT_AllInterruptsEnable (*C enumerator*), 825
drivers_MCX_MCXA_MCXA366._vbat_interrupt_enable.kVBAT_InterruptEnableBandgapTimer0 (*C enumerator*), 825
drivers_MCX_MCXA_MCXA366._vbat_interrupt_enable.kVBAT_InterruptEnableBandgapTimer1 (*C enumerator*), 825
drivers_MCX_MCXA_MCXA366._vbat_interrupt_enable.kVBAT_InterruptEnableInterrupt0 (*C enumerator*), 825
drivers_MCX_MCXA_MCXA366._vbat_interrupt_enable.kVBAT_InterruptEnableInterrupt1 (*C enumerator*), 825
drivers_MCX_MCXA_MCXA366._vbat_interrupt_enable.kVBAT_InterruptEnableInterrupt2 (*C enumerator*), 825
drivers_MCX_MCXA_MCXA366._vbat_interrupt_enable.kVBAT_InterruptEnableInterrupt3 (*C enumerator*), 825
drivers_MCX_MCXA_MCXA366._vbat_interrupt_enable.kVBAT_InterruptEnableLdoReady (*C enumerator*), 825
drivers_MCX_MCXA_MCXA366._vbat_interrupt_enable.kVBAT_InterruptEnableOsc32kReady (*C enumerator*), 825
drivers_MCX_MCXA_MCXA366._vbat_interrupt_enable.kVBAT_InterruptEnablePORDetect (*C enumerator*), 825
drivers_MCX_MCXA_MCXA366._vbat_interrupt_enable.kVBAT_InterruptEnableWakeupPin (*C*

enumerator), 825
drivers_MCX_MCXA_MCXA366._vbat_osc32k_load_capacitance_select (*C enum*), 829
drivers_MCX_MCXA_MCXA366._vbat_osc32k_load_capacitance_select.kVBAT_Osc32kCrystalLoadCap0pF (*C enumerator*), 829
drivers_MCX_MCXA_MCXA366._vbat_osc32k_load_capacitance_select.kVBAT_Osc32kCrystalLoadCap2pF (*C enumerator*), 829
drivers_MCX_MCXA_MCXA366._vbat_osc32k_load_capacitance_select.kVBAT_Osc32kCrystalLoadCap4pF (*C enumerator*), 829
drivers_MCX_MCXA_MCXA366._vbat_osc32k_load_capacitance_select.kVBAT_Osc32kCrystalLoadCap6pF (*C enumerator*), 829
drivers_MCX_MCXA_MCXA366._vbat_osc32k_load_capacitance_select.kVBAT_Osc32kCrystalLoadCap8pF (*C enumerator*), 829
drivers_MCX_MCXA_MCXA366._vbat_osc32k_load_capacitance_select.kVBAT_Osc32kCrystalLoadCap10pF (*C enumerator*), 829
drivers_MCX_MCXA_MCXA366._vbat_osc32k_load_capacitance_select.kVBAT_Osc32kCrystalLoadCap12pF (*C enumerator*), 829
drivers_MCX_MCXA_MCXA366._vbat_osc32k_load_capacitance_select.kVBAT_Osc32kCrystalLoadCap14pF (*C enumerator*), 829
drivers_MCX_MCXA_MCXA366._vbat_osc32k_load_capacitance_select.kVBAT_Osc32kCrystalLoadCap16pF (*C enumerator*), 829
drivers_MCX_MCXA_MCXA366._vbat_osc32k_load_capacitance_select.kVBAT_Osc32kCrystalLoadCap18pF (*C enumerator*), 829
drivers_MCX_MCXA_MCXA366._vbat_osc32k_load_capacitance_select.kVBAT_Osc32kCrystalLoadCap20pF (*C enumerator*), 830
drivers_MCX_MCXA_MCXA366._vbat_osc32k_load_capacitance_select.kVBAT_Osc32kCrystalLoadCap22pF (*C enumerator*), 830
drivers_MCX_MCXA_MCXA366._vbat_osc32k_load_capacitance_select.kVBAT_Osc32kCrystalLoadCap24pF (*C enumerator*), 830
drivers_MCX_MCXA_MCXA366._vbat_osc32k_load_capacitance_select.kVBAT_Osc32kCrystalLoadCap26pF (*C enumerator*), 830
drivers_MCX_MCXA_MCXA366._vbat_osc32k_load_capacitance_select.kVBAT_Osc32kCrystalLoadCap28pF (*C enumerator*), 830
drivers_MCX_MCXA_MCXA366._vbat_osc32k_load_capacitance_select.kVBAT_Osc32kCrystalLoadCap30pF (*C enumerator*), 830
drivers_MCX_MCXA_MCXA366._vbat_osc32k_load_capacitance_select.kVBAT_Osc32kCrystalLoadCapBankDisal (*C enumerator*), 830
drivers_MCX_MCXA_MCXA366._vbat_osc32k_operate_mode (*C enum*), 829
drivers_MCX_MCXA_MCXA366._vbat_osc32k_operate_mode.kVBAT_Osc32kEnabledToLowPowerBackupMode (*C enumerator*), 829
drivers_MCX_MCXA_MCXA366._vbat_osc32k_operate_mode.kVBAT_Osc32kEnabledToLowPowerSwitchedMode (*C enumerator*), 829
drivers_MCX_MCXA_MCXA366._vbat_osc32k_operate_mode.kVBAT_Osc32kEnabledToTransconductanceMode (*C enumerator*), 829
drivers_MCX_MCXA_MCXA366._vbat_osc32k_start_up_time (*C enum*), 830
drivers_MCX_MCXA_MCXA366._vbat_osc32k_start_up_time.kVBAT_Osc32kStartUpTime0P5MSec (*C enumerator*), 830
drivers_MCX_MCXA_MCXA366._vbat_osc32k_start_up_time.kVBAT_Osc32kStartUpTime0P5Sec (*C enumerator*), 830
drivers_MCX_MCXA_MCXA366._vbat_osc32k_start_up_time.kVBAT_Osc32kStartUpTime0P25Sec (*C enumerator*), 830
drivers_MCX_MCXA_MCXA366._vbat_osc32k_start_up_time.kVBAT_Osc32kStartUpTime0P125Sec (*C enumerator*), 830
drivers_MCX_MCXA_MCXA366._vbat_osc32k_start_up_time.kVBAT_Osc32kStartUpTime1Sec (*C enumerator*), 830
drivers_MCX_MCXA_MCXA366._vbat_osc32k_start_up_time.kVBAT_Osc32kStartUpTime2Sec (*C enumerator*), 830
drivers_MCX_MCXA_MCXA366._vbat_osc32k_start_up_time.kVBAT_Osc32kStartUpTime4Sec (*C enumerator*), 830

drivers_MCX_MCXA_MCXA366._vbat_osc32k_start_up_time.kVBAT_Osc32kStartUpTime8Sec (*C enumerator*), 830
drivers_MCX_MCXA_MCXA366._vbat_ram_array (*C enum*), 827
drivers_MCX_MCXA_MCXA366._vbat_ram_array.kVBAT_SramArray0 (*C enumerator*), 827
drivers_MCX_MCXA_MCXA366._vbat_ram_array.kVBAT_SramArray1 (*C enumerator*), 828
drivers_MCX_MCXA_MCXA366._vbat_ram_array.kVBAT_SramArray2 (*C enumerator*), 828
drivers_MCX_MCXA_MCXA366._vbat_ram_array.kVBAT_SramArray3 (*C enumerator*), 828
drivers_MCX_MCXA_MCXA366._vbat_status_flag (*C enum*), 824
drivers_MCX_MCXA_MCXA366._vbat_status_flag.kVBAT_StatusFlagBandgapTimer0 (*C enumerator*), 824
drivers_MCX_MCXA_MCXA366._vbat_status_flag.kVBAT_StatusFlagBandgapTimer1 (*C enumerator*), 824
drivers_MCX_MCXA_MCXA366._vbat_status_flag.kVBAT_StatusFlagInterrupt0Detect (*C enumerator*), 824
drivers_MCX_MCXA_MCXA366._vbat_status_flag.kVBAT_StatusFlagInterrupt1Detect (*C enumerator*), 825
drivers_MCX_MCXA_MCXA366._vbat_status_flag.kVBAT_StatusFlagInterrupt2Detect (*C enumerator*), 825
drivers_MCX_MCXA_MCXA366._vbat_status_flag.kVBAT_StatusFlagInterrupt3Detect (*C enumerator*), 825
drivers_MCX_MCXA_MCXA366._vbat_status_flag.kVBAT_StatusFlagLdoReady (*C enumerator*), 824
drivers_MCX_MCXA_MCXA366._vbat_status_flag.kVBAT_StatusFlagOsc32kReady (*C enumerator*), 824
drivers_MCX_MCXA_MCXA366._vbat_status_flag.kVBAT_StatusFlagPORDetect (*C enumerator*), 824
drivers_MCX_MCXA_MCXA366._vbat_status_flag.kVBAT_StatusFlagWakeupPin (*C enumerator*), 824
drivers_MCX_MCXA_MCXA366._vbat_tamper_config (*C struct*), 845
drivers_MCX_MCXA_MCXA366._vbat_tamper_config.enableTemperatureDetect (*C var*), 846
drivers_MCX_MCXA_MCXA366._vbat_tamper_config.enableVoltageDetect (*C var*), 845
drivers_MCX_MCXA_MCXA366._vbat_tamper_config.lock (*C var*), 846
drivers_MCX_MCXA_MCXA366._vbat_tamper_enable (*C enum*), 826
drivers_MCX_MCXA_MCXA366._vbat_tamper_enable.kVBAT_TamperEnableClockDetect (*C enumerator*), 826
drivers_MCX_MCXA_MCXA366._vbat_tamper_enable.kVBAT_TamperEnableConfigDetect (*C enumerator*), 827
drivers_MCX_MCXA_MCXA366._vbat_tamper_enable.kVBAT_TamperEnablePOR (*C enumerator*), 826
drivers_MCX_MCXA_MCXA366._vbat_tamper_enable.kVBAT_TamperEnableSec0Detect (*C enumerator*), 827
drivers_MCX_MCXA_MCXA366._vbat_tamper_enable.kVBAT_TamperEnableTemperatureDetect (*C enumerator*), 827
drivers_MCX_MCXA_MCXA366._vbat_tamper_enable.kVBAT_TamperEnableVoltageDetect (*C enumerator*), 827
drivers_MCX_MCXA_MCXA366._vbat_wakeup_enable (*C enum*), 826
drivers_MCX_MCXA_MCXA366._vbat_wakeup_enable.kVBAT_AllWakeupsEnable (*C enumerator*), 826
drivers_MCX_MCXA_MCXA366._vbat_wakeup_enable.kVBAT_WakeupEnableBandgapTimer0 (*C enumerator*), 826
drivers_MCX_MCXA_MCXA366._vbat_wakeup_enable.kVBAT_WakeupEnableBandgapTimer1 (*C enumerator*), 826
drivers_MCX_MCXA_MCXA366._vbat_wakeup_enable.kVBAT_WakeupEnableInterrupt0 (*C enumerator*), 826
drivers_MCX_MCXA_MCXA366._vbat_wakeup_enable.kVBAT_WakeupEnableInterrupt1 (*C enumerator*), 826
drivers_MCX_MCXA_MCXA366._vbat_wakeup_enable.kVBAT_WakeupEnableInterrupt2 (*C enumerator*), 826

drivers_MCX_MCXA_MCXA366._vbat_wakeup_enable.kVBAT_WakeupEnableInterrupt3 (*C enumerator*), 826
drivers_MCX_MCXA_MCXA366._vbat_wakeup_enable.kVBAT_WakeupEnableLdoReady (*C enumerator*), 826
drivers_MCX_MCXA_MCXA366._vbat_wakeup_enable.kVBAT_WakeupEnableOsc32kReady (*C enumerator*), 826
drivers_MCX_MCXA_MCXA366._vbat_wakeup_enable.kVBAT_WakeupEnablePORDetect (*C enumerator*), 826
drivers_MCX_MCXA_MCXA366._vbat_wakeup_enable.kVBAT_WakeupEnableWakeupPin (*C enumerator*), 826
drivers_MCX_MCXA_MCXA366._waketimer_config (*C struct*), 982
drivers_MCX_MCXA_MCXA366._waketimer_config.callback (*C var*), 982
drivers_MCX_MCXA_MCXA366._waketimer_config.enableInterrupt (*C var*), 982
drivers_MCX_MCXA_MCXA366._waketimer_config.enableOSCDivide (*C var*), 982
drivers_MCX_MCXA_MCXA366._waketimer_interrupt_enable (*C enum*), 981
drivers_MCX_MCXA_MCXA366._waketimer_interrupt_enable.kWAKETIMER_WakeInterruptEnable (*C enumerator*), 981
drivers_MCX_MCXA_MCXA366._waketimer_status_flags (*C enum*), 981
drivers_MCX_MCXA_MCXA366._waketimer_status_flags.kWAKETIMER_WakeFlag (*C enumerator*), 981
drivers_MCX_MCXA_MCXA366._wuu_external_pin_edge_detection (*C enum*), 984
drivers_MCX_MCXA_MCXA366._wuu_external_pin_edge_detection.kWUU_ExternalPinAnyEdge (*C enumerator*), 985
drivers_MCX_MCXA_MCXA366._wuu_external_pin_edge_detection.kWUU_ExternalPinDisable (*C enumerator*), 985
drivers_MCX_MCXA_MCXA366._wuu_external_pin_edge_detection.kWUU_ExternalPinFallingEdge (*C enumerator*), 985
drivers_MCX_MCXA_MCXA366._wuu_external_pin_edge_detection.kWUU_ExternalPinRisingEdge (*C enumerator*), 985
drivers_MCX_MCXA_MCXA366._wuu_external_wakeup_pin_config (*C struct*), 987
drivers_MCX_MCXA_MCXA366._wuu_external_wakeup_pin_config.edge (*C var*), 987
drivers_MCX_MCXA_MCXA366._wuu_external_wakeup_pin_config.event (*C var*), 987
drivers_MCX_MCXA_MCXA366._wuu_external_wakeup_pin_config.mode (*C var*), 987
drivers_MCX_MCXA_MCXA366._wuu_external_wakeup_pin_event (*C enum*), 985
drivers_MCX_MCXA_MCXA366._wuu_external_wakeup_pin_event.kWUU_ExternalPinDMARequest (*C enumerator*), 985
drivers_MCX_MCXA_MCXA366._wuu_external_wakeup_pin_event.kWUU_ExternalPinInterrupt (*C enumerator*), 985
drivers_MCX_MCXA_MCXA366._wuu_external_wakeup_pin_event.kWUU_ExternalPinTriggerEvent (*C enumerator*), 985
drivers_MCX_MCXA_MCXA366._wuu_external_wakeup_pin_mode (*C enum*), 985
drivers_MCX_MCXA_MCXA366._wuu_external_wakeup_pin_mode.kWUU_ExternalPinActiveAlways (*C enumerator*), 985
drivers_MCX_MCXA_MCXA366._wuu_external_wakeup_pin_mode.kWUU_ExternalPinActiveDSPD (*C enumerator*), 985
drivers_MCX_MCXA_MCXA366._wuu_external_wakeup_pin_mode.kWUU_ExternalPinActiveLowLeakageMode (*C enumerator*), 985
drivers_MCX_MCXA_MCXA366._wuu_filter_edge (*C enum*), 986
drivers_MCX_MCXA_MCXA366._wuu_filter_edge.kWUU_FilterAnyEdge (*C enumerator*), 986
drivers_MCX_MCXA_MCXA366._wuu_filter_edge.kWUU_FilterDisabled (*C enumerator*), 986
drivers_MCX_MCXA_MCXA366._wuu_filter_edge.kWUU_FilterNegedgeEnable (*C enumerator*), 986
drivers_MCX_MCXA_MCXA366._wuu_filter_edge.kWUU_FilterPosedgeEnable (*C enumerator*), 986
drivers_MCX_MCXA_MCXA366._wuu_filter_event (*C enum*), 986
drivers_MCX_MCXA_MCXA366._wuu_filter_event.kWUU_FilterDMARequest (*C enumerator*), 986
drivers_MCX_MCXA_MCXA366._wuu_filter_event.kWUU_FilterInterrupt (*C enumerator*), 986

drivers_MCX_MCXA_MCXA366._wuu_filter_event.kWUU_FilterTriggerEvent (*C enumerator*), 986
drivers_MCX_MCXA_MCXA366._wuu_filter_mode (*C enum*), 986
drivers_MCX_MCXA_MCXA366._wuu_filter_mode.kWUU_FilterActiveAlways (*C enumerator*), 986
drivers_MCX_MCXA_MCXA366._wuu_filter_mode.kWUU_FilterActiveDSPD (*C enumerator*), 986
drivers_MCX_MCXA_MCXA366._wuu_filter_mode.kWUU_FilterActiveLowLeakageMode (*C enumerator*), 986
drivers_MCX_MCXA_MCXA366._wuu_internal_wakeup_module_event (*C enum*), 985
drivers_MCX_MCXA_MCXA366._wuu_internal_wakeup_module_event.kWUU_InternalModuleDMATrigger (*C enumerator*), 986
drivers_MCX_MCXA_MCXA366._wuu_internal_wakeup_module_event.kWUU_InternalModuleInterrupt (*C enumerator*), 985
drivers_MCX_MCXA_MCXA366._wuu_pin_filter_config (*C struct*), 987
drivers_MCX_MCXA_MCXA366._wuu_pin_filter_config.edge (*C var*), 988
drivers_MCX_MCXA_MCXA366._wuu_pin_filter_config.event (*C var*), 988
drivers_MCX_MCXA_MCXA366._wuu_pin_filter_config.mode (*C var*), 988
drivers_MCX_MCXA_MCXA366._wuu_pin_filter_config.pinIndex (*C var*), 988
drivers_MCX_MCXA_MCXA366._wwdt_config (*C struct*), 991
drivers_MCX_MCXA_MCXA366._wwdt_config.clockFreq_Hz (*C var*), 991
drivers_MCX_MCXA_MCXA366._wwdt_config.enableWatchdogProtect (*C var*), 991
drivers_MCX_MCXA_MCXA366._wwdt_config.enableWatchdogReset (*C var*), 991
drivers_MCX_MCXA_MCXA366._wwdt_config.enableWwdt (*C var*), 991
drivers_MCX_MCXA_MCXA366._wwdt_config.timeoutValue (*C var*), 991
drivers_MCX_MCXA_MCXA366._wwdt_config.warningValue (*C var*), 991
drivers_MCX_MCXA_MCXA366._wwdt_config.windowValue (*C var*), 991
drivers_MCX_MCXA_MCXA366._wwdt_status_flags_t (*C enum*), 990
drivers_MCX_MCXA_MCXA366._wwdt_status_flags_t.kWWDT_TimeoutFlag (*C enumerator*), 991
drivers_MCX_MCXA_MCXA366._wwdt_status_flags_t.kWWDT_WarningFlag (*C enumerator*), 991
drivers_MCX_MCXA_MCXA366.A_FORMAT_BITS_PER_FRAME_DATA (*C macro*), 366
drivers_MCX_MCXA_MCXA366.A_FORMAT_BITS_PER_FRAME_WHOLE (*C macro*), 366
drivers_MCX_MCXA_MCXA366.A_FORMAT_CDF (*C macro*), 362
drivers_MCX_MCXA_MCXA366.A_FORMAT_CDF_MASK_COMMAND_CODE (*C macro*), 364
drivers_MCX_MCXA_MCXA366.A_FORMAT_CDF_MASK_CRC_CODE (*C macro*), 364
drivers_MCX_MCXA_MCXA366.A_FORMAT_CDF_MASK_ENCODER_ADDR (*C macro*), 364
drivers_MCX_MCXA_MCXA366.A_FORMAT_CDF_MASK_FRAME_CODE (*C macro*), 364
drivers_MCX_MCXA_MCXA366.A_FORMAT_CDF_MASK_SYNC_CODE (*C macro*), 364
drivers_MCX_MCXA_MCXA366.A_FORMAT_CDF_SHIFT_COMMAND_CODE (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_CDF_SHIFT_CRC_CODE (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_CDF_SHIFT_ENCODER_ADDR (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_CDF_SHIFT_FRAME_CODE (*C macro*), 364
drivers_MCX_MCXA_MCXA366.A_FORMAT_CDF_SHIFT_SYNC_CODE (*C macro*), 364
drivers_MCX_MCXA_MCXA366.A_FORMAT_CRC_POLY_COMMAND_DATA (*C macro*), 364
drivers_MCX_MCXA_MCXA366.A_FORMAT_CRC_POLY_ENCODER_DATA (*C macro*), 364
drivers_MCX_MCXA_MCXA366.A_FORMAT_CRC_RANGE_IN_CDF (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_CRC_RANGE_IN_MDF (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_ENCODER_MAX_NUM (*C macro*), 366
drivers_MCX_MCXA_MCXA366.A_FORMAT_FRAME_CODE_CDF (*C macro*), 362
drivers_MCX_MCXA_MCXA366.A_FORMAT_FRAME_CODE_MDF0 (*C macro*), 362
drivers_MCX_MCXA_MCXA366.A_FORMAT_FRAME_CODE_MDF1 (*C macro*), 362
drivers_MCX_MCXA_MCXA366.A_FORMAT_FRAME_CODE_MDF2 (*C macro*), 362
drivers_MCX_MCXA_MCXA366.A_FORMAT_GET_CMD_CODE_CDF (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_GET_CMD_CODE_IF (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_GET_CRC_CODE_CDF (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_GET_CRC_DATA_CDF (*C macro*), 365

drivers_MCX_MCXA_MCXA366.A_FORMAT_GET_CRC_DATA_MDF (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_GET_ENC_ADDR_CDF (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_GET_ENC_ADDR_IF (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_GET_ENC_STAT_IF (*C macro*), 366
drivers_MCX_MCXA_MCXA366.A_FORMAT_IF_MASK_COMMAND_CODE (*C macro*), 364
drivers_MCX_MCXA_MCXA366.A_FORMAT_IF_MASK_ENCODER_ADDR (*C macro*), 364
drivers_MCX_MCXA_MCXA366.A_FORMAT_IF_MASK_ENCODER_STAT (*C macro*), 364
drivers_MCX_MCXA_MCXA366.A_FORMAT_MDF_MASK_CRC_CODE (*C macro*), 364
drivers_MCX_MCXA_MCXA366.A_FORMAT_MDF_MASK_DATA_BIT (*C macro*), 364
drivers_MCX_MCXA_MCXA366.A_FORMAT_MDF_MASK_FRAME_CODE (*C macro*), 364
drivers_MCX_MCXA_MCXA366.A_FORMAT_MDF_MASK_SYNC_CODE (*C macro*), 364
drivers_MCX_MCXA_MCXA366.A_FORMAT_MDF_SHIFT_CRC_CODE (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_MDF_SHIFT_DATA_BIT (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_MDF_SHIFT_FRAME_CODE (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_MDF_SHIFT_SYNC_CODE (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_PACK_CDF (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_PACK_MDF (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_ABS_FULL_40BIT (*C macro*), 362
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_ABS_LOWER_17BIT (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_ABS_LOWER_24BIT (*C macro*), 362
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_ABS_LOWER_24BIT_STAT (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_ABS_LOWER_24BIT_TEMP (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_ABS_UPPER_24BIT (*C macro*), 362
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_CLEAR_MULTI_TURN (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_CLEAR_STAT_FLAG (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_CLEAR_STAT_MULTI (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_ENCODER_STAT (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_ID_CODE_READ1 (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_ID_CODE_READ2 (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_ID_CODE_WRITE1 (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_ID_CODE_WRITE2 (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_MEMORY_READ (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_MEMORY_WRITE (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_PRESET_SINGLE_TURN_0 (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_SET_ENCODER_ADDR1 (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_SET_ENCODER_ADDR2 (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_IT_TEMPERATURE_10BIT (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_MT_ABS_FULL_40BIT (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_MT_ABS_LOWER_17BIT (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_MT_ABS_LOWER_24BIT (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_MT_ABS_LOWER_24BIT_STAT (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_MT_ABS_LOWER_24BIT_TEMP (*C macro*), 364
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_MT_ABS_UPPER_24BIT (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_REQ_MT_ENCODER_STAT (*C macro*), 363
drivers_MCX_MCXA_MCXA366.A_FORMAT_RETRY_TIMES (*C macro*), 366
drivers_MCX_MCXA_MCXA366.A_FORMAT_SET_CRC_CODE_CDF (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_SET_CRC_CODE_MDF (*C macro*), 365
drivers_MCX_MCXA_MCXA366.A_FORMAT_SYNC_CODE_CMD (*C macro*), 362
drivers_MCX_MCXA_MCXA366.A_FORMAT_SYNC_CODE_IF (*C macro*), 362
drivers_MCX_MCXA_MCXA366.A_FORMAT_TIMER_COMPARE_VALUE (*C macro*), 366

drivers_MCX_MCXA_MCXA366.A_FORMAT_TIMER_DR_INDEX (*C macro*), 366
drivers_MCX_MCXA_MCXA366.A_FORMAT_TIMER_RX_CLOCK_INDEX (*C macro*), 366
drivers_MCX_MCXA_MCXA366.A_FORMAT_TIMER_RX_INDEX (*C macro*), 366
drivers_MCX_MCXA_MCXA366.A_FORMAT_TIMER_TX_CLOCK_INDEX (*C macro*), 366
drivers_MCX_MCXA_MCXA366.A_FORMAT_TIMER_TX_INDEX (*C macro*), 366
drivers_MCX_MCXA_MCXA366.ADC_OFSTRIM_OFSTRIM_MAX (*C macro*), 640
drivers_MCX_MCXA_MCXA366.ADC_OFSTRIM_OFSTRIM_SIGN (*C macro*), 640
drivers_MCX_MCXA_MCXA366.AOI (*C macro*), 203
drivers_MCX_MCXA_MCXA366.AOI_Deinit (*C function*), 201
drivers_MCX_MCXA_MCXA366.aoi_event_config_t (*C type*), 203
drivers_MCX_MCXA_MCXA366.aoi_event_t (*C type*), 203
drivers_MCX_MCXA_MCXA366.AOI_GetEventLogicConfig (*C function*), 201
drivers_MCX_MCXA_MCXA366.AOI_Init (*C function*), 201
drivers_MCX_MCXA_MCXA366.aoi_input_config_t (*C type*), 203
drivers_MCX_MCXA_MCXA366.AOI_SetEventLogicConfig (*C function*), 201
drivers_MCX_MCXA_MCXA366.ARRAY_SIZE (*C macro*), 630
drivers_MCX_MCXA_MCXA366.AT_CACHE_LINE_SECTION (*C macro*), 617
drivers_MCX_MCXA_MCXA366.AT_CACHE_LINE_SECTION_INIT (*C macro*), 618
drivers_MCX_MCXA_MCXA366.AT_NONCACHEABLE_SECTION (*C macro*), 617
drivers_MCX_MCXA_MCXA366.AT_NONCACHEABLE_SECTION_ALIGN (*C macro*), 617
drivers_MCX_MCXA_MCXA366.AT_NONCACHEABLE_SECTION_ALIGN_INIT (*C macro*), 617
drivers_MCX_MCXA_MCXA366.AT_NONCACHEABLE_SECTION_INIT (*C macro*), 617
drivers_MCX_MCXA_MCXA366.AT_QUICKACCESS_SECTION_CODE (*C macro*), 618
drivers_MCX_MCXA_MCXA366.AT_QUICKACCESS_SECTION_DATA (*C macro*), 618
drivers_MCX_MCXA_MCXA366.AT_QUICKACCESS_SECTION_DATA_ALIGN (*C macro*), 618
drivers_MCX_MCXA_MCXA366.baudRate_bps (*C var*), 367
drivers_MCX_MCXA_MCXA366.buffersize (*C var*), 915
drivers_MCX_MCXA_MCXA366.callback (*C var*), 368, 470
drivers_MCX_MCXA_MCXA366.cameraParam (*C var*), 915
drivers_MCX_MCXA_MCXA366.CDOG_Add (*C function*), 206
drivers_MCX_MCXA_MCXA366.CDOG_Add1 (*C function*), 206
drivers_MCX_MCXA_MCXA366.CDOG_Add16 (*C function*), 207
drivers_MCX_MCXA_MCXA366.CDOG_Add256 (*C function*), 207
drivers_MCX_MCXA_MCXA366.CDOG_Check (*C function*), 206
drivers_MCX_MCXA_MCXA366.cdog_config_t (*C struct*), 209
drivers_MCX_MCXA_MCXA366.CDOG_Deinit (*C function*), 205
drivers_MCX_MCXA_MCXA366.CDOG_GetDefaultConfig (*C function*), 205
drivers_MCX_MCXA_MCXA366.CDOG_Init (*C function*), 205
drivers_MCX_MCXA_MCXA366.CDOG_ReadPersistent (*C function*), 207
drivers_MCX_MCXA_MCXA366.CDOG_Set (*C function*), 206
drivers_MCX_MCXA_MCXA366.CDOG_Start (*C function*), 206
drivers_MCX_MCXA_MCXA366.CDOG_Stop (*C function*), 205
drivers_MCX_MCXA_MCXA366.CDOG_Sub (*C function*), 207
drivers_MCX_MCXA_MCXA366.CDOG_Sub1 (*C function*), 207
drivers_MCX_MCXA_MCXA366.CDOG_Sub16 (*C function*), 207
drivers_MCX_MCXA_MCXA366.CDOG_Sub256 (*C function*), 207
drivers_MCX_MCXA_MCXA366.CDOG_WritePersistent (*C function*), 207
drivers_MCX_MCXA_MCXA366.clock_mode (*C var*), 782
drivers_MCX_MCXA_MCXA366.CMC_BLR_LOCK_FIELD_WIDTH (*C macro*), 774
drivers_MCX_MCXA_MCXA366.CMC_BLR_LOCK_IDX (*C macro*), 774
drivers_MCX_MCXA_MCXA366.CMC_BLR_LOCK_IDX_MASK (*C macro*), 774
drivers_MCX_MCXA_MCXA366.CMC_BLR_LOCK_IDX_SHIFT (*C macro*), 774
drivers_MCX_MCXA_MCXA366.CMC_CheckBootRomStatusRegWriteLocked (*C function*), 779
drivers_MCX_MCXA_MCXA366.CMC_ClearCoreClockGatedStatus (*C function*), 775
drivers_MCX_MCXA_MCXA366.CMC_ClearISPMODEPinLogic (*C function*), 778
drivers_MCX_MCXA_MCXA366.CMC_ClearStickySystemResetStatus (*C function*), 775
drivers_MCX_MCXA_MCXA366.CMC_ClearSystemResetInterruptFlags (*C function*), 777

drivers_MCX_MCXA_MCXA366.cmc_clock_mode_t (*C type*), 774
drivers_MCX_MCXA_MCXA366.CMC_ConfigFlashMode (*C function*), 781
drivers_MCX_MCXA_MCXA366.CMC_ConfigResetPin (*C function*), 777
drivers_MCX_MCXA_MCXA366.cmc_core_clock_gate_status_t (*C type*), 774
drivers_MCX_MCXA_MCXA366.CMC_DisableSystemResetInterrupt (*C function*), 777
drivers_MCX_MCXA_MCXA366.CMC_EnableDebugOperation (*C function*), 781
drivers_MCX_MCXA_MCXA366.CMC_EnableNonMaskablePinInterrupt (*C function*), 778
drivers_MCX_MCXA_MCXA366.CMC_EnableSystemResetInterrupt (*C function*), 777
drivers_MCX_MCXA_MCXA366.CMC_EnterLowPowerMode (*C function*), 781
drivers_MCX_MCXA_MCXA366.CMC_ForceBootConfiguration (*C function*), 778
drivers_MCX_MCXA_MCXA366.CMC_GetBootRomStatus (*C function*), 778, 779
drivers_MCX_MCXA_MCXA366.CMC_GetClockMode (*C function*), 775
drivers_MCX_MCXA_MCXA366.CMC_GetCoreClockGatedStatus (*C function*), 774
drivers_MCX_MCXA_MCXA366.CMC_GetISPMODEPinLogic (*C function*), 778
drivers_MCX_MCXA_MCXA366.CMC_GetMAINPowerMode (*C function*), 777
drivers_MCX_MCXA_MCXA366.CMC_GetResetCount (*C function*), 776
drivers_MCX_MCXA_MCXA366.CMC_GetStickySystemResetStatus (*C function*), 775
drivers_MCX_MCXA_MCXA366.CMC_GetSystemResetInterruptFlags (*C function*), 777
drivers_MCX_MCXA_MCXA366.CMC_GetSystemResetStatus (*C function*), 775
drivers_MCX_MCXA_MCXA366.CMC_GetWakeupSource (*C function*), 775
drivers_MCX_MCXA_MCXA366.CMC_GlobalEnterLowPowerMode (*C function*), 781
drivers_MCX_MCXA_MCXA366.CMC_LockClockModeSetting (*C function*), 774
drivers_MCX_MCXA_MCXA366.CMC_LockPowerModeProtectionSetting (*C function*), 776
drivers_MCX_MCXA_MCXA366.CMC_LockWriteOperationToBootRomStatusReg (*C function*), 779
drivers_MCX_MCXA_MCXA366.cmc_low_power_mode_t (*C type*), 774
drivers_MCX_MCXA_MCXA366.CMC_PostExitLowPowerMode (*C function*), 781
drivers_MCX_MCXA_MCXA366.cmc_power_domain_config_t (*C type*), 774
drivers_MCX_MCXA_MCXA366.CMC_PowerOffSRAMAllMode (*C function*), 780
drivers_MCX_MCXA_MCXA366.CMC_PowerOffSRAMLowPowerOnly (*C function*), 780
drivers_MCX_MCXA_MCXA366.CMC_PowerOnSRAMAllMode (*C function*), 780
drivers_MCX_MCXA_MCXA366.CMC_PowerOnSRAMLowPowerOnly (*C function*), 780
drivers_MCX_MCXA_MCXA366.CMC_PreEnterLowPowerMode (*C function*), 781
drivers_MCX_MCXA_MCXA366.cmc_reset_pin_config_t (*C type*), 774
drivers_MCX_MCXA_MCXA366.CMC_SetBootRomStatus (*C function*), 778
drivers_MCX_MCXA_MCXA366.CMC_SetClockMode (*C function*), 774
drivers_MCX_MCXA_MCXA366.CMC_SetGlobalPowerMode (*C function*), 776
drivers_MCX_MCXA_MCXA366.CMC_SetMAINPowerMode (*C function*), 776
drivers_MCX_MCXA_MCXA366.CMC_SetPowerModeProtection (*C function*), 776
drivers_MCX_MCXA_MCXA366.CMC_WriteBootRomStatusReg (*C function*), 779
drivers_MCX_MCXA_MCXA366.CONFIG_MAU_ENABLE_CMSIS_DSP_API (*C macro*), 768
drivers_MCX_MCXA_MCXA366.CONFIG_MAU_ENABLE_CMSIS_DSP_ARM_SQRT_F32_API (*C macro*), 768
drivers_MCX_MCXA_MCXA366.cos_addr (*C var*), 764
drivers_MCX_MCXA_MCXA366.COUNT_TO_MSEC (*C macro*), 617
drivers_MCX_MCXA_MCXA366.COUNT_TO_USEC (*C macro*), 617
drivers_MCX_MCXA_MCXA366.crc_bits_t (*C type*), 210
drivers_MCX_MCXA_MCXA366.crc_config_t (*C type*), 210
drivers_MCX_MCXA_MCXA366.CRC_Deinit (*C function*), 210
drivers_MCX_MCXA_MCXA366.CRC_DRIVER_USE_CRC16_CCIT_FALSE_AS_DEFAULT (*C macro*), 211
drivers_MCX_MCXA_MCXA366.CRC_Get16bitResult (*C function*), 211
drivers_MCX_MCXA_MCXA366.CRC_Get32bitResult (*C function*), 211
drivers_MCX_MCXA_MCXA366.CRC_GetDefaultConfig (*C function*), 211
drivers_MCX_MCXA_MCXA366.CRC_Init (*C function*), 210
drivers_MCX_MCXA_MCXA366.crc_result_t (*C type*), 210
drivers_MCX_MCXA_MCXA366.CRC_WriteData (*C function*), 211
drivers_MCX_MCXA_MCXA366.ctimer_callback_t (*C type*), 219
drivers_MCX_MCXA_MCXA366.ctimer_callback_type_t (*C enum*), 218

drivers_MCX_MCXA_MCXA366.ctimer_callback_type_t.kCTIMER_MultipleCallback (*C enumerator*), 218
drivers_MCX_MCXA_MCXA366.ctimer_callback_type_t.kCTIMER_SingleCallback (*C enumerator*), 218
drivers_MCX_MCXA_MCXA366.ctimer_capture_channel_t (*C type*), 218
drivers_MCX_MCXA_MCXA366.ctimer_capture_edge_t (*C type*), 218
drivers_MCX_MCXA_MCXA366.CTIMER_ClearStatusFlags (*C function*), 215
drivers_MCX_MCXA_MCXA366.ctimer_config_t (*C type*), 219
drivers_MCX_MCXA_MCXA366.CTIMER_Deinit (*C function*), 212
drivers_MCX_MCXA_MCXA366.CTIMER_DisableInterrupts (*C function*), 215
drivers_MCX_MCXA_MCXA366.CTIMER_EnableFallingEdgeCapture (*C function*), 221
drivers_MCX_MCXA_MCXA366.CTIMER_EnableInterrupts (*C function*), 214
drivers_MCX_MCXA_MCXA366.CTIMER_EnableMatchChannelReload (*C function*), 221
drivers_MCX_MCXA_MCXA366.CTIMER_EnableResetMatchChannel (*C function*), 221
drivers_MCX_MCXA_MCXA366.CTIMER_EnableRisingEdgeCapture (*C function*), 221
drivers_MCX_MCXA_MCXA366.CTIMER_EnableStopMatchChannel (*C function*), 221
drivers_MCX_MCXA_MCXA366.ctimer_external_match_t (*C type*), 218
drivers_MCX_MCXA_MCXA366.CTIMER_GetCaptureValue (*C function*), 220
drivers_MCX_MCXA_MCXA366.CTIMER_GetDefaultConfig (*C function*), 213
drivers_MCX_MCXA_MCXA366.CTIMER_GetEnabledInterrupts (*C function*), 215
drivers_MCX_MCXA_MCXA366.CTIMER_GetOutputMatchStatus (*C function*), 219
drivers_MCX_MCXA_MCXA366.CTIMER_GetStatusFlags (*C function*), 215
drivers_MCX_MCXA_MCXA366.CTIMER_GetTimerCountValue (*C function*), 220
drivers_MCX_MCXA_MCXA366.CTIMER_Init (*C function*), 212
drivers_MCX_MCXA_MCXA366.ctimer_interrupt_enable_t (*C type*), 218
drivers_MCX_MCXA_MCXA366.ctimer_match_config_t (*C type*), 219
drivers_MCX_MCXA_MCXA366.ctimer_match_output_control_t (*C type*), 218
drivers_MCX_MCXA_MCXA366.ctimer_match_t (*C type*), 218
drivers_MCX_MCXA_MCXA366.CTIMER_RegisterCallBack (*C function*), 220
drivers_MCX_MCXA_MCXA366.CTIMER_Reset (*C function*), 220
drivers_MCX_MCXA_MCXA366.CTIMER_SetPrescale (*C function*), 220
drivers_MCX_MCXA_MCXA366.CTIMER_SetShadowValue (*C function*), 222
drivers_MCX_MCXA_MCXA366.CTIMER_SetupCapture (*C function*), 219
drivers_MCX_MCXA_MCXA366.CTIMER_SetupMatch (*C function*), 219
drivers_MCX_MCXA_MCXA366.CTIMER_SetupPwm (*C function*), 213
drivers_MCX_MCXA_MCXA366.CTIMER_SetupPwmPeriod (*C function*), 213
drivers_MCX_MCXA_MCXA366.CTIMER_StartTimer (*C function*), 215
drivers_MCX_MCXA_MCXA366.ctimer_status_flags_t (*C type*), 218
drivers_MCX_MCXA_MCXA366.CTIMER_StopTimer (*C function*), 215
drivers_MCX_MCXA_MCXA366.ctimer_timer_mode_t (*C type*), 218
drivers_MCX_MCXA_MCXA366.CTIMER_UpdatePwmDutycycle (*C function*), 214
drivers_MCX_MCXA_MCXA366.CTIMER_UpdatePwmPulsePeriod (*C function*), 214
drivers_MCX_MCXA_MCXA366.DAC_ClearReset (*C function*), 223
drivers_MCX_MCXA_MCXA366.DAC_ClearStatusFlags (*C function*), 224
drivers_MCX_MCXA_MCXA366.dac_config_t (*C type*), 229
drivers_MCX_MCXA_MCXA366.DAC_Deinit (*C function*), 223
drivers_MCX_MCXA_MCXA366.DAC_DisableInterrupts (*C function*), 224
drivers_MCX_MCXA_MCXA366.DAC_DoSoftwareTriggerFIFO (*C function*), 225
drivers_MCX_MCXA_MCXA366.DAC_Enable (*C function*), 224
drivers_MCX_MCXA_MCXA366.DAC_EnableDMA (*C function*), 224
drivers_MCX_MCXA_MCXA366.DAC_EnableInterrupts (*C function*), 224
drivers_MCX_MCXA_MCXA366.dac_fifo_trigger_mode_t (*C type*), 228
drivers_MCX_MCXA_MCXA366.dac_fifo_work_mode_t (*C type*), 228
drivers_MCX_MCXA_MCXA366.DAC_GetDefaultConfig (*C function*), 223
drivers_MCX_MCXA_MCXA366.DAC_GetFIFOReadPointer (*C function*), 225
drivers_MCX_MCXA_MCXA366.DAC_GetFIFOWritePointer (*C function*), 225
drivers_MCX_MCXA_MCXA366.DAC_GetStatusFlags (*C function*), 224
drivers_MCX_MCXA_MCXA366.DAC_Init (*C function*), 223

drivers_MCX_MCXA_MCXA366.dac_reference_current_source_t (*C type*), 228
drivers_MCX_MCXA_MCXA366.dac_reference_current_trim_t (*C type*), 228
drivers_MCX_MCXA_MCXA366.dac_reference_voltage_source_t (*C type*), 228
drivers_MCX_MCXA_MCXA366.DAC_SetData (*C function*), 224
drivers_MCX_MCXA_MCXA366.DAC_SetReset (*C function*), 223
drivers_MCX_MCXA_MCXA366.data (*C var*), 367, 469
drivers_MCX_MCXA_MCXA366.dataSize (*C var*), 368, 469
drivers_MCX_MCXA_MCXA366.DEBUG_CONSOLE_DEVICE_TYPE_FLEXCOMM (*C macro*), 615
drivers_MCX_MCXA_MCXA366.DEBUG_CONSOLE_DEVICE_TYPE_IUART (*C macro*), 615
drivers_MCX_MCXA_MCXA366.DEBUG_CONSOLE_DEVICE_TYPE_LPSCI (*C macro*), 614
drivers_MCX_MCXA_MCXA366.DEBUG_CONSOLE_DEVICE_TYPE_LPUART (*C macro*), 614
drivers_MCX_MCXA_MCXA366.DEBUG_CONSOLE_DEVICE_TYPE_MINI_USART (*C macro*), 615
drivers_MCX_MCXA_MCXA366.DEBUG_CONSOLE_DEVICE_TYPE_NONE (*C macro*), 614
drivers_MCX_MCXA_MCXA366.DEBUG_CONSOLE_DEVICE_TYPE_QSCI (*C macro*), 615
drivers_MCX_MCXA_MCXA366.DEBUG_CONSOLE_DEVICE_TYPE_SWO (*C macro*), 615
drivers_MCX_MCXA_MCXA366.DEBUG_CONSOLE_DEVICE_TYPE_UART (*C macro*), 614
drivers_MCX_MCXA_MCXA366.DEBUG_CONSOLE_DEVICE_TYPE_USBCDC (*C macro*), 614
drivers_MCX_MCXA_MCXA366.DEBUG_CONSOLE_DEVICE_TYPE_VUSART (*C macro*), 615
drivers_MCX_MCXA_MCXA366.DisableGlobalIRQ (*C function*), 629
drivers_MCX_MCXA_MCXA366.DisableIRQ (*C function*), 628
drivers_MCX_MCXA_MCXA366.DLC_LENGTH_DECODE (*C macro*), 332
drivers_MCX_MCXA_MCXA366.DMA_ATTR_DMOD (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_ATTR_DMOD_MASK (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_ATTR_DSIZE (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_ATTR_DSIZE_MASK (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_ATTR_DSIZE_SHIFT (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_ATTR_SMOD (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_ATTR_SMOD_MASK (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_ATTR_SSIZE (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_ATTR_SSIZE_MASK (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_ATTR_SSIZE_SHIFT (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_BITER_ELINKNO_BITER_MASK (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_BITER_ELINKYES_ELINK_MASK (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_BITER_ELINKYES_LINKCH (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_BITER_ELINKYES_LINKCH_MASK (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_CH_CSR_SIGNEXT_MASK (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_CH_CSR_SIGNEXT_SHIFT (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_CH_CSR_SWAP_MASK (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_CH_CSR_SWAP_SHIFT (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_CH_MATTR_RCACHE (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_CH_MATTR_WCACHE (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_CH_MUX_SOURCE (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_CH_SBR_EMI_MASK (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_CH_SBR_EMI_SHIFT (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_CH_SBR_INSTR_MASK (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_CH_SBR_INSTR_SHIFT (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_CITER_ELINKNO_CITER_MASK (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_CITER_ELINKNO_CITER_SHIFT (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_CITER_ELINKNO_ELINK_MASK (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_CITER_ELINKYES_CITER_MASK (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_CITER_ELINKYES_CITER_SHIFT (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_CITER_ELINKYES_ELINK_MASK (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_CITER_ELINKYES_LINKCH (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_CITER_ELINKYES_LINKCH_MASK (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_CLEAR_DONE_STATUS (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_CLEAR_ERROR_STATUS (*C macro*), 267

drivers_MCX_MCXA_MCXA366.DMA_CLEAR_INT_STATUS (*C macro*), 268
drivers_MCX_MCXA_MCXA366.DMA_CORE_MP_CSR_EDBG (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_CORE_MP_CSR_EDBG_MASK (*C macro*), 264
drivers_MCX_MCXA_MCXA366.DMA_CORE_MP_CSR_ERCA (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_CORE_MP_CSR_ERCA_MASK (*C macro*), 264
drivers_MCX_MCXA_MCXA366.DMA_CORE_MP_CSR_GCLC (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_CORE_MP_CSR_GCLC_MASK (*C macro*), 264
drivers_MCX_MCXA_MCXA366.DMA_CORE_MP_CSR_GMRC (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_CORE_MP_CSR_GMRC_MASK (*C macro*), 264
drivers_MCX_MCXA_MCXA366.DMA_CORE_MP_CSR_HAE (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_CORE_MP_CSR_HAE_MASK (*C macro*), 264
drivers_MCX_MCXA_MCXA366.DMA_CORE_MP_CSR_HALT (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_CORE_MP_CSR_HALT_MASK (*C macro*), 264
drivers_MCX_MCXA_MCXA366.DMA_CSR_BWC (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_CSR_BWC_MASK (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_CSR_DREQ (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_CSR_DREQ_MASK (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_CSR_ESG_MASK (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_CSR_INTHALF_MASK (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_CSR_INTMAJOR_MASK (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_CSR_MAJORELINK_MASK (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_CSR_MAJORLINKCH (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_CSR_MAJORLINKCH_MASK (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_CSR_START_MASK (*C macro*), 265
drivers_MCX_MCXA_MCXA366.DMA_DCHPRI_INDEX (*C macro*), 259
drivers_MCX_MCXA_MCXA366.DMA_DISABLE_ERROR_INT (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_DISABLE_HALF_INT (*C macro*), 268
drivers_MCX_MCXA_MCXA366.DMA_DISABLE_MAJOR_INT (*C macro*), 268
drivers_MCX_MCXA_MCXA366.DMA_ENABLE_ERROR_INT (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_ENABLE_HALF_INT (*C macro*), 268
drivers_MCX_MCXA_MCXA366.DMA_ENABLE_MAJOR_INT (*C macro*), 268
drivers_MCX_MCXA_MCXA366.DMA_ERR_DAE_FLAG (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_ERR_DBE_FLAG (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_ERR_DOE_FLAG (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_ERR_ECX_FLAG (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_ERR_ERRCHAN_FLAG (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_ERR_FLAG (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_ERR_NCE_FLAG (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_ERR_SAE_FLAG (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_ERR_SBE_FLAG (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_ERR_SGE_FLAG (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_ERR_SOE_FLAG (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_GET_DONE_STATUS (*C macro*), 267
drivers_MCX_MCXA_MCXA366.DMA_GET_ERROR_STATUS (*C macro*), 268
drivers_MCX_MCXA_MCXA366.DMA_GET_INT_STATUS (*C macro*), 268
drivers_MCX_MCXA_MCXA366.DMA_MAX_TRANSFER_COUNT (*C macro*), 725
drivers_MCX_MCXA_MCXA366.DMA_NBYTES_MLOFFNO_NBYTES (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_NBYTES_MLOFFNO_NBYTES_MASK (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_NBYTES_MLOFFYES_DMLOE (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_NBYTES_MLOFFYES_DMLOE_MASK (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_NBYTES_MLOFFYES_MLOFF (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_NBYTES_MLOFFYES_MLOFF_MASK (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_NBYTES_MLOFFYES_NBYTES (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_NBYTES_MLOFFYES_SMLOE (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DMA_NBYTES_MLOFFYES_SMLOE_MASK (*C macro*), 266
drivers_MCX_MCXA_MCXA366.DRPinIndex (*C var*), 367, 469
drivers_MCX_MCXA_MCXA366.E_RX_FIFO (*C macro*), 335
drivers_MCX_MCXA_MCXA366.edma4_core_tcd_t (*C type*), 264

drivers_MCX_MCXA_MCXA366.edma5_core_tcd_t (*C type*), 264
drivers_MCX_MCXA_MCXA366.EDMA_AbortTransfer (*C function*), 248
drivers_MCX_MCXA_MCXA366.EDMA_ALLOCATE_TCD (*C macro*), 259
drivers_MCX_MCXA_MCXA366.edma_bandwidth_t (*C type*), 256
drivers_MCX_MCXA_MCXA366.edma_callback (*C type*), 258
drivers_MCX_MCXA_MCXA366.edma_channel_access_type_t (*C type*), 257
drivers_MCX_MCXA_MCXA366.EDMA_CHANNEL_BASE (*C macro*), 268
drivers_MCX_MCXA_MCXA366.edma_channel_config_t (*C type*), 257
drivers_MCX_MCXA_MCXA366.edma_channel_link_type_t (*C type*), 256
drivers_MCX_MCXA_MCXA366.edma_channel_memory_attribute (*C enum*), 254
drivers_MCX_MCXA_MCXA366.edma_channel_memory_attribute_t (*C type*), 257
drivers_MCX_MCXA_MCXA366.edma_channel_memory_attribute.kEDMA_ChannelNoWriteNoReadCacheableBuff (*C enumerator*), 254
drivers_MCX_MCXA_MCXA366.edma_channel_memory_attribute.kEDMA_ChannelNoWriteNoReadCacheableNoB (*C enumerator*), 254
drivers_MCX_MCXA_MCXA366.edma_channel_memory_attribute.kEDMA_ChannelNoWriteNoReadNoCacheBuffe (*C enumerator*), 254
drivers_MCX_MCXA_MCXA366.edma_channel_memory_attribute.kEDMA_ChannelNoWriteNoReadNoCacheNoBu (*C enumerator*), 254
drivers_MCX_MCXA_MCXA366.edma_channel_memory_attribute.kEDMA_ChannelNoWriteReadCacheableBuffera (*C enumerator*), 255
drivers_MCX_MCXA_MCXA366.edma_channel_memory_attribute.kEDMA_ChannelNoWriteReadCacheableNoBuff (*C enumerator*), 254
drivers_MCX_MCXA_MCXA366.edma_channel_memory_attribute.kEDMA_ChannelNoWriteReadNoCacheBufferab (*C enumerator*), 254
drivers_MCX_MCXA_MCXA366.edma_channel_memory_attribute.kEDMA_ChannelNoWriteReadNoCacheNoBuffe (*C enumerator*), 254
drivers_MCX_MCXA_MCXA366.edma_channel_memory_attribute.kEDMA_ChannelWriteNoReadCacheableBuffera (*C enumerator*), 255
drivers_MCX_MCXA_MCXA366.edma_channel_memory_attribute.kEDMA_ChannelWriteNoReadCacheableNoBuff (*C enumerator*), 255
drivers_MCX_MCXA_MCXA366.edma_channel_memory_attribute.kEDMA_ChannelWriteNoReadNoCacheBufferab (*C enumerator*), 255
drivers_MCX_MCXA_MCXA366.edma_channel_memory_attribute.kEDMA_ChannelWriteNoReadNoCacheNoBuffe (*C enumerator*), 255
drivers_MCX_MCXA_MCXA366.edma_channel_memory_attribute.kEDMA_ChannelWriteReadCacheableBufferable (*C enumerator*), 255
drivers_MCX_MCXA_MCXA366.edma_channel_memory_attribute.kEDMA_ChannelWriteReadCacheableNoBuffer (*C enumerator*), 255
drivers_MCX_MCXA_MCXA366.edma_channel_memory_attribute.kEDMA_ChannelWriteReadNoCacheBufferable (*C enumerator*), 255
drivers_MCX_MCXA_MCXA366.edma_channel_memory_attribute.kEDMA_ChannelWriteReadNoCacheNoBuffer (*C enumerator*), 255
drivers_MCX_MCXA_MCXA366.edma_channel_Preemption_config_t (*C type*), 257
drivers_MCX_MCXA_MCXA366.edma_channel_protection_level_t (*C type*), 257
drivers_MCX_MCXA_MCXA366.edma_channel_swap_size_t (*C type*), 257
drivers_MCX_MCXA_MCXA366.EDMA_ChannelType (*C type*), 264
drivers_MCX_MCXA_MCXA366.EDMA_ClearChannelStatusFlags (*C function*), 243
drivers_MCX_MCXA_MCXA366.edma_config_t (*C type*), 258
drivers_MCX_MCXA_MCXA366.EDMA_ConfigChannelSoftwareTCD (*C function*), 235
drivers_MCX_MCXA_MCXA366.EDMA_ConfigChannelSoftwareTCDExt (*C function*), 239
drivers_MCX_MCXA_MCXA366.EDMA_CORE_BASE (*C macro*), 268
drivers_MCX_MCXA_MCXA366.edma_core_channel_t (*C type*), 264
drivers_MCX_MCXA_MCXA366.edma_core_mp_t (*C type*), 264
drivers_MCX_MCXA_MCXA366.edma_core_tcd_t (*C type*), 264
drivers_MCX_MCXA_MCXA366.EDMA_CreateHandle (*C function*), 243
drivers_MCX_MCXA_MCXA366.EDMA_Deinit (*C function*), 230
drivers_MCX_MCXA_MCXA366.EDMA_DisableChannelInterrupts (*C function*), 235

drivers_MCX_MCXA_MCXA366.EDMA_DisableChannelRequest (*C function*), 242
drivers_MCX_MCXA_MCXA366.EDMA_EnableAsyncRequest (*C function*), 234
drivers_MCX_MCXA_MCXA366.EDMA_EnableAutoStopRequest (*C function*), 235
drivers_MCX_MCXA_MCXA366.EDMA_EnableChannelInterrupts (*C function*), 235
drivers_MCX_MCXA_MCXA366.EDMA_EnableChannelMasterIDReplication (*C function*), 232
drivers_MCX_MCXA_MCXA366.EDMA_EnableChannelRequest (*C function*), 242
drivers_MCX_MCXA_MCXA366.EDMA_GetChannelStatusFlags (*C function*), 243
drivers_MCX_MCXA_MCXA366.EDMA_GetChannelSystemBusInformation (*C function*), 232
drivers_MCX_MCXA_MCXA366.EDMA_GetDefaultConfig (*C function*), 230
drivers_MCX_MCXA_MCXA366.EDMA_GetErrorStatusFlags (*C function*), 243
drivers_MCX_MCXA_MCXA366.EDMA_GetNextTCDAddress (*C function*), 248
drivers_MCX_MCXA_MCXA366.EDMA_GetRemainingMajorLoopCount (*C function*), 242
drivers_MCX_MCXA_MCXA366.EDMA_GetUnusedTCDNumber (*C function*), 248
drivers_MCX_MCXA_MCXA366.edma_handle_t (*C type*), 258
drivers_MCX_MCXA_MCXA366.EDMA_HandleIRQ (*C function*), 248
drivers_MCX_MCXA_MCXA366.EDMA_Init (*C function*), 230
drivers_MCX_MCXA_MCXA366.EDMA_InitChannel (*C function*), 230
drivers_MCX_MCXA_MCXA366.EDMA_InstallTCD (*C function*), 230
drivers_MCX_MCXA_MCXA366.EDMA_InstallTCDMemory (*C function*), 244
drivers_MCX_MCXA_MCXA366.edma_minor_offset_config_t (*C type*), 257
drivers_MCX_MCXA_MCXA366.edma_modulo_t (*C type*), 256
drivers_MCX_MCXA_MCXA366.EDMA_MP_BASE (*C macro*), 268
drivers_MCX_MCXA_MCXA366.EDMA_PrepareTransfer (*C function*), 245
drivers_MCX_MCXA_MCXA366.EDMA_PrepareTransferConfig (*C function*), 244
drivers_MCX_MCXA_MCXA366.EDMA_PrepareTransferTCD (*C function*), 245
drivers_MCX_MCXA_MCXA366.EDMA_ResetChannel (*C function*), 232
drivers_MCX_MCXA_MCXA366.EDMA_SetBandWidth (*C function*), 234
drivers_MCX_MCXA_MCXA366.EDMA_SetCallback (*C function*), 244
drivers_MCX_MCXA_MCXA366.EDMA_SetChannelAccessType (*C function*), 231
drivers_MCX_MCXA_MCXA366.EDMA_SetChannelLink (*C function*), 233
drivers_MCX_MCXA_MCXA366.EDMA_SetChannelMemoryAttribute (*C function*), 231
drivers_MCX_MCXA_MCXA366.EDMA_SetChannelMux (*C function*), 231
drivers_MCX_MCXA_MCXA366.EDMA_SetChannelPreemptionConfig (*C function*), 233
drivers_MCX_MCXA_MCXA366.EDMA_SetChannelProtectionLevel (*C function*), 232
drivers_MCX_MCXA_MCXA366.EDMA_SetChannelSignExtension (*C function*), 231
drivers_MCX_MCXA_MCXA366.EDMA_SetChannelSwapSize (*C function*), 231
drivers_MCX_MCXA_MCXA366.EDMA_SetMajorOffsetConfig (*C function*), 235
drivers_MCX_MCXA_MCXA366.EDMA_SetMinorOffsetConfig (*C function*), 233
drivers_MCX_MCXA_MCXA366.EDMA_SetModulo (*C function*), 234
drivers_MCX_MCXA_MCXA366.EDMA_SetTransferConfig (*C function*), 233
drivers_MCX_MCXA_MCXA366.EDMA_StartTransfer (*C function*), 248
drivers_MCX_MCXA_MCXA366.EDMA_StopTransfer (*C function*), 248
drivers_MCX_MCXA_MCXA366.EDMA_SubmitLoopTransfer (*C function*), 247
drivers_MCX_MCXA_MCXA366.EDMA_SubmitTransfer (*C function*), 247
drivers_MCX_MCXA_MCXA366.EDMA_SubmitTransferTCD (*C function*), 246
drivers_MCX_MCXA_MCXA366.EDMA_TCD_ALIGN_SIZE (*C macro*), 268
drivers_MCX_MCXA_MCXA366.EDMA_TCD_ATTR (*C macro*), 268
drivers_MCX_MCXA_MCXA366.EDMA_TCD_BASE (*C macro*), 268
drivers_MCX_MCXA_MCXA366.EDMA_TCD_BITER (*C macro*), 268
drivers_MCX_MCXA_MCXA366.EDMA_TCD_CITER (*C macro*), 268
drivers_MCX_MCXA_MCXA366.EDMA_TCD_CSR (*C macro*), 268
drivers_MCX_MCXA_MCXA366.EDMA_TCD_DADDR (*C macro*), 268
drivers_MCX_MCXA_MCXA366.EDMA_TCD_DLAST_SGA (*C macro*), 268
drivers_MCX_MCXA_MCXA366.EDMA_TCD_DOFF (*C macro*), 268
drivers_MCX_MCXA_MCXA366.EDMA_TCD_NBYTES (*C macro*), 268
drivers_MCX_MCXA_MCXA366.EDMA_TCD_SADDR (*C macro*), 268
drivers_MCX_MCXA_MCXA366.EDMA_TCD_SLAST (*C macro*), 268
drivers_MCX_MCXA_MCXA366.EDMA_TCD_SOFF (*C macro*), 268

drivers_MCX_MCXA_MCXA366.edma_tcd_t (*C type*), 257
drivers_MCX_MCXA_MCXA366.EDMA_TCD_TYPE (*C macro*), 268
drivers_MCX_MCXA_MCXA366.edma_tcd_type_t (*C type*), 264
drivers_MCX_MCXA_MCXA366.EDMA_TcdDisableInterrupts (*C function*), 238
drivers_MCX_MCXA_MCXA366.EDMA_TcdDisableInterruptsExt (*C function*), 242
drivers_MCX_MCXA_MCXA366.EDMA_TcdEnableAutoStopRequest (*C function*), 238
drivers_MCX_MCXA_MCXA366.EDMA_TcdEnableAutoStopRequestExt (*C function*), 241
drivers_MCX_MCXA_MCXA366.EDMA_TcdEnableInterrupts (*C function*), 238
drivers_MCX_MCXA_MCXA366.EDMA_TcdEnableInterruptsExt (*C function*), 241
drivers_MCX_MCXA_MCXA366.EDMA_TcdInit (*C function*), 249
drivers_MCX_MCXA_MCXA366.EDMA_TcdReset (*C function*), 236
drivers_MCX_MCXA_MCXA366.EDMA_TcdResetExt (*C function*), 239
drivers_MCX_MCXA_MCXA366.EDMA_TcdSetBandWidth (*C function*), 237
drivers_MCX_MCXA_MCXA366.EDMA_TcdSetBandWidthExt (*C function*), 241
drivers_MCX_MCXA_MCXA366.EDMA_TcdSetChannelLink (*C function*), 237
drivers_MCX_MCXA_MCXA366.EDMA_TcdSetChannelLinkExt (*C function*), 240
drivers_MCX_MCXA_MCXA366.EDMA_TcdSetMajorOffsetConfig (*C function*), 239
drivers_MCX_MCXA_MCXA366.EDMA_TcdSetMajorOffsetConfigExt (*C function*), 242
drivers_MCX_MCXA_MCXA366.EDMA_TcdSetMinorOffsetConfig (*C function*), 237
drivers_MCX_MCXA_MCXA366.EDMA_TcdSetMinorOffsetConfigExt (*C function*), 240
drivers_MCX_MCXA_MCXA366.EDMA_TcdSetModulo (*C function*), 238
drivers_MCX_MCXA_MCXA366.EDMA_TcdSetModuloExt (*C function*), 241
drivers_MCX_MCXA_MCXA366.EDMA_TcdSetTransferConfig (*C function*), 236
drivers_MCX_MCXA_MCXA366.EDMA_TcdSetTransferConfigExt (*C function*), 239
drivers_MCX_MCXA_MCXA366.EDMA_TCDType (*C type*), 264
drivers_MCX_MCXA_MCXA366.edma_transfer_config_t (*C type*), 257
drivers_MCX_MCXA_MCXA366.edma_transfer_size_t (*C type*), 256
drivers_MCX_MCXA_MCXA366.edma_transfer_type_t (*C type*), 256
drivers_MCX_MCXA_MCXA366.EDMA_TriggerChannelStart (*C function*), 242
drivers_MCX_MCXA_MCXA366.EDMA_Type (*C type*), 264
drivers_MCX_MCXA_MCXA366.EIM_Deinit (*C function*), 273
drivers_MCX_MCXA_MCXA366.EIM_Init (*C function*), 273
drivers_MCX_MCXA_MCXA366.enableA_Format (*C var*), 367
drivers_MCX_MCXA_MCXA366.enableFastAccess (*C var*), 367, 469
drivers_MCX_MCXA_MCXA366.EnableGlobalIRQ (*C function*), 630
drivers_MCX_MCXA_MCXA366.enableInDebug (*C var*), 367, 469
drivers_MCX_MCXA_MCXA366.enableInDoze (*C var*), 367, 469
drivers_MCX_MCXA_MCXA366.EnableIRQ (*C function*), 628
drivers_MCX_MCXA_MCXA366.EnableIRQWithPriority (*C function*), 629
drivers_MCX_MCXA_MCXA366.enableT_Format (*C var*), 469
drivers_MCX_MCXA_MCXA366.ENCODER_ADDRESS (*C macro*), 366
drivers_MCX_MCXA_MCXA366.ENCODER_ADDRESS_IS_MT (*C macro*), 366
drivers_MCX_MCXA_MCXA366.ENCODER_ADDRESS_IT (*C macro*), 366
drivers_MCX_MCXA_MCXA366.ENCODER_ADDRESS_MT (*C macro*), 366
drivers_MCX_MCXA_MCXA366.ENHANCED_RX_FIFO_FSCH (*C macro*), 333
drivers_MCX_MCXA_MCXA366.EQDC_ClearBufferedRegisterLoadUpdateMode (*C function*), 275
drivers_MCX_MCXA_MCXA366.EQDC_ClearEqdcLdok (*C function*), 275
drivers_MCX_MCXA_MCXA366.EQDC_ClearStatusFlags (*C function*), 276
drivers_MCX_MCXA_MCXA366.eqdc_config_t (*C type*), 290
drivers_MCX_MCXA_MCXA366.eqdc_count_direction_flag_t (*C type*), 290
drivers_MCX_MCXA_MCXA366.eqdc_count_mode_t (*C type*), 289
drivers_MCX_MCXA_MCXA366.EQDC_CTRL_INT_EN (*C macro*), 290
drivers_MCX_MCXA_MCXA366.EQDC_CTRL_INT_FLAGS (*C macro*), 290
drivers_MCX_MCXA_MCXA366.EQDC_CTRL_W1C_FLAGS (*C macro*), 290
drivers_MCX_MCXA_MCXA366.EQDC_Deinit (*C function*), 274
drivers_MCX_MCXA_MCXA366.EQDC_DisableInterrupts (*C function*), 276
drivers_MCX_MCXA_MCXA366.EQDC_DoSoftwareLoadInitialPositionValue (*C function*), 276
drivers_MCX_MCXA_MCXA366.EQDC_EnableDMA (*C function*), 275

drivers_MCX_MCXA_MCXA366.EQDC_EnableInterrupts (*C function*), 276
drivers_MCX_MCXA_MCXA366.EQDC_EnableWatchdog (*C function*), 274
drivers_MCX_MCXA_MCXA366.eqdc_filter_sample_count_t (*C type*), 289
drivers_MCX_MCXA_MCXA366.EQDC_GetBufferedPositionDifferencePeriod (*C function*), 281
drivers_MCX_MCXA_MCXA366.EQDC_GetDefaultConfig (*C function*), 273
drivers_MCX_MCXA_MCXA366.EQDC_GetEqdcLdok (*C function*), 275
drivers_MCX_MCXA_MCXA366.EQDC_GetHoldLastEdgeTime (*C function*), 281
drivers_MCX_MCXA_MCXA366.EQDC_GetHoldPosition (*C function*), 279
drivers_MCX_MCXA_MCXA366.EQDC_GetHoldPosition1 (*C function*), 279
drivers_MCX_MCXA_MCXA366.EQDC_GetHoldPosition2 (*C function*), 279
drivers_MCX_MCXA_MCXA366.EQDC_GetHoldPosition3 (*C function*), 280
drivers_MCX_MCXA_MCXA366.EQDC_GetHoldPositionDifference (*C function*), 280
drivers_MCX_MCXA_MCXA366.EQDC_GetHoldPositionDifferencePeriod (*C function*), 282
drivers_MCX_MCXA_MCXA366.EQDC_GetHoldRevolution (*C function*), 281
drivers_MCX_MCXA_MCXA366.EQDC_GetLastCountDirection (*C function*), 276
drivers_MCX_MCXA_MCXA366.EQDC_GetLastEdgeTime (*C function*), 281
drivers_MCX_MCXA_MCXA366.EQDC_GetPosition (*C function*), 279
drivers_MCX_MCXA_MCXA366.EQDC_GetPositionDifference (*C function*), 280
drivers_MCX_MCXA_MCXA366.EQDC_GetPositionDifferencePeriod (*C function*), 281
drivers_MCX_MCXA_MCXA366.EQDC_GetRevolution (*C function*), 280
drivers_MCX_MCXA_MCXA366.EQDC_GetSignalStatusFlags (*C function*), 276
drivers_MCX_MCXA_MCXA366.EQDC_GetStatusFlags (*C function*), 276
drivers_MCX_MCXA_MCXA366.eqdc_home_enable_init_pos_counter_mode_t (*C type*), 288
drivers_MCX_MCXA_MCXA366.eqdc_index_preset_init_pos_counter_mode_t (*C type*), 289
drivers_MCX_MCXA_MCXA366.EQDC_Init (*C function*), 273
drivers_MCX_MCXA_MCXA366.EQDC_INTCTRL_INT_EN (*C macro*), 290
drivers_MCX_MCXA_MCXA366.EQDC_INTCTRL_INT_FLAGS (*C macro*), 290
drivers_MCX_MCXA_MCXA366.EQDC_INTCTRL_W1C_FLAGS (*C macro*), 290
drivers_MCX_MCXA_MCXA366.eqdc_operate_mode_t (*C type*), 289
drivers_MCX_MCXA_MCXA366.eqdc_output_pulse_mode_t (*C type*), 289
drivers_MCX_MCXA_MCXA366.eqdc_prescaler_t (*C type*), 290
drivers_MCX_MCXA_MCXA366.eqdc_revolution_count_condition_t (*C type*), 289
drivers_MCX_MCXA_MCXA366.EQDC_SetBufferedRegisterLoadUpdateMode (*C function*), 275
drivers_MCX_MCXA_MCXA366.EQDC_SetCountMode (*C function*), 274
drivers_MCX_MCXA_MCXA366.EQDC_SetEqdcLdok (*C function*), 275
drivers_MCX_MCXA_MCXA366.EQDC_SetInitialPositionValue (*C function*), 277
drivers_MCX_MCXA_MCXA366.EQDC_SetOperateMode (*C function*), 274
drivers_MCX_MCXA_MCXA366.EQDC_SetPositionCompare0Value (*C function*), 277
drivers_MCX_MCXA_MCXA366.EQDC_SetPositionCompare1Value (*C function*), 278
drivers_MCX_MCXA_MCXA366.EQDC_SetPositionCompare2Value (*C function*), 278
drivers_MCX_MCXA_MCXA366.EQDC_SetPositionCompare3Value (*C function*), 278
drivers_MCX_MCXA_MCXA366.EQDC_SetPositionCounterValue (*C function*), 277
drivers_MCX_MCXA_MCXA366.EQDC_SetPositionModulusValue (*C function*), 277
drivers_MCX_MCXA_MCXA366.EQDC_SetWatchdogTimeout (*C function*), 275
drivers_MCX_MCXA_MCXA366.ERM_ClearInterruptStatus (*C function*), 293
drivers_MCX_MCXA_MCXA366.ERM_Deinit (*C function*), 293
drivers_MCX_MCXA_MCXA366.ERM_DisableInterrupts (*C function*), 293
drivers_MCX_MCXA_MCXA366.ERM_EnableInterrupts (*C function*), 293
drivers_MCX_MCXA_MCXA366.ERM_GetInterruptStatus (*C function*), 293
drivers_MCX_MCXA_MCXA366.ERM_GetMemoryErrorAddr (*C function*), 294
drivers_MCX_MCXA_MCXA366.ERM_Init (*C function*), 293
drivers_MCX_MCXA_MCXA366.FLEXCAN_BusoffErrorHandleIRQ (*C function*), 316
drivers_MCX_MCXA_MCXA366.flexcan_byte_error_syndrome_t (*C type*), 330
drivers_MCX_MCXA_MCXA366.FLEXCAN_CalculateImprovedTimingValues (*C function*), 296
drivers_MCX_MCXA_MCXA366.FLEXCAN_CALLBACK (*C macro*), 335
drivers_MCX_MCXA_MCXA366.flexcan_capture_point_t (*C type*), 330
drivers_MCX_MCXA_MCXA366.FLEXCAN_ClearHigh64MbStatusFlags (*C function*), 303
drivers_MCX_MCXA_MCXA366.FLEXCAN_ClearMbStatusFlags (*C function*), 303

drivers_MCX_MCXA_MCXA366.FLEXCAN_ClearStatusFlags (*C function*), 303
drivers_MCX_MCXA_MCXA366.flexcan_clock_source_t (*C type*), 329
drivers_MCX_MCXA_MCXA366.flexcan_config_t (*C type*), 331
drivers_MCX_MCXA_MCXA366.FLEXCAN_Deinit (*C function*), 297
drivers_MCX_MCXA_MCXA366.FLEXCAN_DisableHigh64MbInterrupts (*C function*), 305
drivers_MCX_MCXA_MCXA366.FLEXCAN_DisableInterrupts (*C function*), 304
drivers_MCX_MCXA_MCXA366.FLEXCAN_DisableMbInterrupts (*C function*), 305
drivers_MCX_MCXA_MCXA366.flexcan_edma_handle_t (*C type*), 352
drivers_MCX_MCXA_MCXA366.flexcan_edma_transfer_callback_t (*C type*), 353
drivers_MCX_MCXA_MCXA366.flexcan_efifo_dma_per_read_length_t (*C type*), 330
drivers_MCX_MCXA_MCXA366.FLEXCAN_EFIFO_INT_MASK (*C macro*), 334
drivers_MCX_MCXA_MCXA366.FLEXCAN_EFIFO_INT_UNMASK (*C macro*), 334
drivers_MCX_MCXA_MCXA366.FLEXCAN_EFIFO_STATUS_MASK (*C macro*), 334
drivers_MCX_MCXA_MCXA366.FLEXCAN_EFIFO_STATUS_UNMASK (*C macro*), 335
drivers_MCX_MCXA_MCXA366.FLEXCAN_Enable (*C function*), 305
drivers_MCX_MCXA_MCXA366.FLEXCAN_EnableHigh64MbInterrupts (*C function*), 305
drivers_MCX_MCXA_MCXA366.FLEXCAN_EnableInterrupts (*C function*), 304
drivers_MCX_MCXA_MCXA366.FLEXCAN_EnableMbInterrupts (*C function*), 305
drivers_MCX_MCXA_MCXA366.FLEXCAN_EnableRxFifoDMA (*C function*), 305
drivers_MCX_MCXA_MCXA366.flexcan_endianness_t (*C type*), 329
drivers_MCX_MCXA_MCXA366.flexcan_enhanced_rx_fifo_config_t (*C type*), 331
drivers_MCX_MCXA_MCXA366.FLEXCAN_ENHANCED_RX_FIFO_EXT_FILTER_WITH_RANGE_HIGH (*C macro*), 334
drivers_MCX_MCXA_MCXA366.FLEXCAN_ENHANCED_RX_FIFO_EXT_FILTER_WITH_RANGE_LOW (*C macro*), 334
drivers_MCX_MCXA_MCXA366.flexcan_enhanced_rx_fifo_ext_id_filter_t (*C type*), 331
drivers_MCX_MCXA_MCXA366.FLEXCAN_ENHANCED_RX_FIFO_EXT_MASK_AND_FILTER_HIGH (*C macro*), 334
drivers_MCX_MCXA_MCXA366.FLEXCAN_ENHANCED_RX_FIFO_EXT_MASK_AND_FILTER_LOW (*C macro*), 334
drivers_MCX_MCXA_MCXA366.FLEXCAN_ENHANCED_RX_FIFO_EXT_TWO_FILTERS_HIGH (*C macro*), 334
drivers_MCX_MCXA_MCXA366.FLEXCAN_ENHANCED_RX_FIFO_EXT_TWO_FILTERS_LOW (*C macro*), 334
drivers_MCX_MCXA_MCXA366.FLEXCAN_ENHANCED_RX_FIFO_INT_FLAG (*C macro*), 335
drivers_MCX_MCXA_MCXA366.FLEXCAN_ENHANCED_RX_FIFO_STD_FILTER_WITH_RANGE (*C macro*), 334
drivers_MCX_MCXA_MCXA366.flexcan_enhanced_rx_fifo_std_id_filter_t (*C type*), 331
drivers_MCX_MCXA_MCXA366.FLEXCAN_ENHANCED_RX_FIFO_STD_MASK_AND_FILTER (*C macro*), 334
drivers_MCX_MCXA_MCXA366.FLEXCAN_ENHANCED_RX_FIFO_STD_TWO_FILTERS (*C macro*), 334
drivers_MCX_MCXA_MCXA366.FLEXCAN_EnhancedRxFifoHandleIRQ (*C function*), 315
drivers_MCX_MCXA_MCXA366.FLEXCAN_EnterFreezeMode (*C function*), 295
drivers_MCX_MCXA_MCXA366.FLEXCAN_ERROR_AND_STATUS_INT_FLAG (*C macro*), 335
drivers_MCX_MCXA_MCXA366.FLEXCAN_ExitFreezeMode (*C function*), 295
drivers_MCX_MCXA_MCXA366.flexcan_fd_frame_t (*C type*), 330
drivers_MCX_MCXA_MCXA366.FLEXCAN_FDCalculateImprovedTimingValues (*C function*), 297
drivers_MCX_MCXA_MCXA366.FLEXCAN_FDInit (*C function*), 297
drivers_MCX_MCXA_MCXA366.flexcan_fifo_transfer_t (*C type*), 331
drivers_MCX_MCXA_MCXA366.flexcan_frame_format_t (*C type*), 329
drivers_MCX_MCXA_MCXA366.flexcan_frame_t (*C type*), 330
drivers_MCX_MCXA_MCXA366.flexcan_frame_type_t (*C type*), 329
drivers_MCX_MCXA_MCXA366.FLEXCAN_GetBusErrCount (*C function*), 303
drivers_MCX_MCXA_MCXA366.FLEXCAN_GetDefaultConfig (*C function*), 298
drivers_MCX_MCXA_MCXA366.FLEXCAN_GetEnhancedFifoDataCount (*C function*), 304

drivers_MCX_MCXA_MCXA366.FLEXCAN_GetFDMailboxOffset (*C function*), 295
drivers_MCX_MCXA_MCXA366.FLEXCAN_GetHigh64MbStatusFlags (*C function*), 303
drivers_MCX_MCXA_MCXA366.FLEXCAN_GetHighResolutionTimeStamp (*C function*), 314
drivers_MCX_MCXA_MCXA366.FLEXCAN_GetInstance (*C function*), 296
drivers_MCX_MCXA_MCXA366.FLEXCAN_GetMbStatusFlags (*C function*), 303
drivers_MCX_MCXA_MCXA366.FLEXCAN_GetMemoryErrorReportStatus (*C function*), 304
drivers_MCX_MCXA_MCXA366.FLEXCAN_GetPNMatchCount (*C function*), 304
drivers_MCX_MCXA_MCXA366.FLEXCAN_GetRxFifoHeadAddr (*C function*), 305
drivers_MCX_MCXA_MCXA366.FLEXCAN_GetStatusFlags (*C function*), 302
drivers_MCX_MCXA_MCXA366.FLEXCAN_GetTimeStamp (*C function*), 314
drivers_MCX_MCXA_MCXA366.flexcan_handle_t (*C type*), 331
drivers_MCX_MCXA_MCXA366.FLEXCAN_ID_EXT (*C macro*), 332
drivers_MCX_MCXA_MCXA366.FLEXCAN_ID_STD (*C macro*), 332
drivers_MCX_MCXA_MCXA366.FLEXCAN_Init (*C function*), 296
drivers_MCX_MCXA_MCXA366.FLEXCAN_IsInstanceHasFDMode (*C function*), 295
drivers_MCX_MCXA_MCXA366.FLEXCAN_MB_BUSY_TIMEOUT (*C macro*), 332
drivers_MCX_MCXA_MCXA366.flexcan_mb_size_t (*C type*), 330
drivers_MCX_MCXA_MCXA366.flexcan_MB_timestamp_base_t (*C type*), 330
drivers_MCX_MCXA_MCXA366.flexcan_mb_transfer_t (*C type*), 331
drivers_MCX_MCXA_MCXA366.FLEXCAN_MbHandleIRQ (*C function*), 315
drivers_MCX_MCXA_MCXA366.FLEXCAN_MECR_INT_MASK (*C macro*), 335
drivers_MCX_MCXA_MCXA366.FLEXCAN_MECR_INT_UNMASK (*C macro*), 335
drivers_MCX_MCXA_MCXA366.FLEXCAN_MECR_STATUS_MASK (*C macro*), 335
drivers_MCX_MCXA_MCXA366.FLEXCAN_MECR_STATUS_UNMASK (*C macro*), 335
drivers_MCX_MCXA_MCXA366.flexcan_memory_access_type_t (*C type*), 330
drivers_MCX_MCXA_MCXA366.FLEXCAN_MEMORY_ERROR_INT_FLAG (*C macro*), 335
drivers_MCX_MCXA_MCXA366.flexcan_memory_error_report_status_t (*C type*), 330
drivers_MCX_MCXA_MCXA366.flexcan_memory_error_type_t (*C type*), 330
drivers_MCX_MCXA_MCXA366.FLEXCAN_MemoryErrorHandleIRQ (*C function*), 316
drivers_MCX_MCXA_MCXA366.FLEXCAN_MODULE_TIMEOUT (*C macro*), 332
drivers_MCX_MCXA_MCXA366.flexcan_pn_config_t (*C type*), 331
drivers_MCX_MCXA_MCXA366.FLEXCAN_PN_EXT_MASK (*C macro*), 334
drivers_MCX_MCXA_MCXA366.FLEXCAN_PN_INT_MASK (*C macro*), 334
drivers_MCX_MCXA_MCXA366.FLEXCAN_PN_INT_UNMASK (*C macro*), 334
drivers_MCX_MCXA_MCXA366.flexcan_pn_match_mode_t (*C type*), 331
drivers_MCX_MCXA_MCXA366.flexcan_pn_match_source_t (*C type*), 331
drivers_MCX_MCXA_MCXA366.FLEXCAN_PN_STATUS_MASK (*C macro*), 334
drivers_MCX_MCXA_MCXA366.FLEXCAN_PN_STATUS_UNMASK (*C macro*), 334
drivers_MCX_MCXA_MCXA366.FLEXCAN_PN_STD_MASK (*C macro*), 334
drivers_MCX_MCXA_MCXA366.FLEXCAN_PNWAKE_UP_FLAG (*C macro*), 335
drivers_MCX_MCXA_MCXA366.FLEXCAN_PNWakeUpHandleIRQ (*C function*), 316
drivers_MCX_MCXA_MCXA366.FLEXCAN_POLLING_TIMEOUT (*C macro*), 332
drivers_MCX_MCXA_MCXA366.FLEXCAN_PrepareTransfConfiguration (*C function*), 350
drivers_MCX_MCXA_MCXA366.FLEXCAN_ReadEnhancedRxFifo (*C function*), 307
drivers_MCX_MCXA_MCXA366.FLEXCAN_ReadFDRxMb (*C function*), 307
drivers_MCX_MCXA_MCXA366.FLEXCAN_ReadPNWakeUpMB (*C function*), 307
drivers_MCX_MCXA_MCXA366.FLEXCAN_ReadRxFifo (*C function*), 307
drivers_MCX_MCXA_MCXA366.FLEXCAN_ReadRxMb (*C function*), 306
drivers_MCX_MCXA_MCXA366.flexcan_rx_fifo_config_t (*C type*), 331
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_EXT_FILTER_TYPE_A (*C macro*), 333
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_EXT_FILTER_TYPE_B_HIGH (*C macro*), 333
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_EXT_FILTER_TYPE_B_LOW (*C macro*), 333
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_EXT_FILTER_TYPE_C_HIGH (*C macro*), 333
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_EXT_FILTER_TYPE_C_LOW (*C macro*), 333

drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_EXT_FILTER_TYPE_C_MID_HIGH (*C macro*), 333
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_EXT_FILTER_TYPE_C_MID_LOW (*C macro*), 333
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_EXT_MASK_TYPE_A (*C macro*), 332
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_EXT_MASK_TYPE_B_HIGH (*C macro*), 332
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_EXT_MASK_TYPE_B_LOW (*C macro*), 333
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_EXT_MASK_TYPE_C_HIGH (*C macro*), 333
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_EXT_MASK_TYPE_C_LOW (*C macro*), 333
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_EXT_MASK_TYPE_C_MID_HIGH (*C macro*), 333
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_EXT_MASK_TYPE_C_MID_LOW (*C macro*), 333
drivers_MCX_MCXA_MCXA366.flexcan_rx_fifo_filter_type_t (*C type*), 330
drivers_MCX_MCXA_MCXA366.flexcan_rx_fifo_priority_t (*C type*), 330
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_STD_FILTER_TYPE_A (*C macro*), 333
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_STD_FILTER_TYPE_B_HIGH (*C macro*), 333
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_STD_FILTER_TYPE_B_LOW (*C macro*), 333
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_STD_FILTER_TYPE_C_HIGH (*C macro*), 333
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_STD_FILTER_TYPE_C_LOW (*C macro*), 333
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_STD_FILTER_TYPE_C_MID_HIGH (*C macro*), 333
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_STD_FILTER_TYPE_C_MID_LOW (*C macro*), 333
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_STD_MASK_TYPE_A (*C macro*), 332
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_STD_MASK_TYPE_B_HIGH (*C macro*), 332
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_STD_MASK_TYPE_B_LOW (*C macro*), 332
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_STD_MASK_TYPE_C_HIGH (*C macro*), 332
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_STD_MASK_TYPE_C_LOW (*C macro*), 332
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_STD_MASK_TYPE_C_MID_HIGH (*C macro*), 332
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_FIFO_STD_MASK_TYPE_C_MID_LOW (*C macro*), 332
drivers_MCX_MCXA_MCXA366.flexcan_rx_mb_config_t (*C type*), 331
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_MB_EXT_MASK (*C macro*), 332
drivers_MCX_MCXA_MCXA366.FLEXCAN_RX_MB_STD_MASK (*C macro*), 332
drivers_MCX_MCXA_MCXA366.FLEXCAN_SetBitRate (*C function*), 298
drivers_MCX_MCXA_MCXA366.FLEXCAN_SetEnhancedRxFifoConfig (*C function*), 302
drivers_MCX_MCXA_MCXA366.FLEXCAN_SetFDBitRate (*C function*), 299
drivers_MCX_MCXA_MCXA366.FLEXCAN_SetFDMbID (*C function*), 301
drivers_MCX_MCXA_MCXA366.FLEXCAN_SetFDRxMbConfig (*C function*), 301
drivers_MCX_MCXA_MCXA366.FLEXCAN_SetFDTimingConfig (*C function*), 298
drivers_MCX_MCXA_MCXA366.FLEXCAN_SetFDTxMbConfig (*C function*), 300
drivers_MCX_MCXA_MCXA366.FLEXCAN_SetMbID (*C function*), 300
drivers_MCX_MCXA_MCXA366.FLEXCAN_SetPNConfig (*C function*), 302
drivers_MCX_MCXA_MCXA366.FLEXCAN_SetRemoteResponseMbConfig (*C function*), 301

drivers_MCX_MCXA_MCXA366.FLEXCAN_SetRxFifoConfig (*C function*), 301
drivers_MCX_MCXA_MCXA366.FLEXCAN_SetRxFifoGlobalMask (*C function*), 299
drivers_MCX_MCXA_MCXA366.FLEXCAN_SetRxIndividualMask (*C function*), 299
drivers_MCX_MCXA_MCXA366.FLEXCAN_SetRxMbConfig (*C function*), 300
drivers_MCX_MCXA_MCXA366.FLEXCAN_SetRxMbGlobalMask (*C function*), 299
drivers_MCX_MCXA_MCXA366.FLEXCAN_SetTimingConfig (*C function*), 298
drivers_MCX_MCXA_MCXA366.FLEXCAN_SetTxMbConfig (*C function*), 300
drivers_MCX_MCXA_MCXA366.FLEXCAN_StartTransferDatafromRxFIFO (*C function*), 351
drivers_MCX_MCXA_MCXA366.flexcan_timing_config_t (*C type*), 330
drivers_MCX_MCXA_MCXA366.flexcan_transfer_callback_t (*C type*), 331
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferAbortReceive (*C function*), 315
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferAbortReceiveEnhancedFifo (*C function*), 315
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferAbortReceiveFifo (*C function*), 315
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferAbortReceiveFifoEDMA (*C function*), 352
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferAbortSend (*C function*), 314
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferCreateHandle (*C function*), 311
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferCreateHandleEDMA (*C function*), 350
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferFDAbortReceive (*C function*), 309
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferFDAbortSend (*C function*), 309
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferFDReceiveBlocking (*C function*), 308
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferFDReceiveNonBlocking (*C function*), 309
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferFDSendBlocking (*C function*), 308
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferFDSendNonBlocking (*C function*), 309
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferGetReceiveEnhancedFifoCount (*C function*), 314
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferGetReceiveEnhancedFifoCountEMDA (*C function*), 352
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferGetReceiveFifoCount (*C function*), 313
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferGetReceiveFifoCountEMDA (*C function*), 351
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferHandleIRQ (*C function*), 315
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferReceiveBlocking (*C function*), 310
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferReceiveEnhancedFifoBlocking (*C function*), 311
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferReceiveEnhancedFifoEDMA (*C function*), 352
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferReceiveEnhancedFifoNonBlocking (*C function*), 314
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferReceiveFifoBlocking (*C function*), 310
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferReceiveFifoEDMA (*C function*), 351
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferReceiveFifoNonBlocking (*C function*), 313
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferReceiveNonBlocking (*C function*), 312
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferRemoteRequestNonBlocking (*C function*), 312
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferRemoteResponseNonBlocking (*C function*), 312
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferSendBlocking (*C function*), 310
drivers_MCX_MCXA_MCXA366.FLEXCAN_TransferSendNonBlocking (*C function*), 311
drivers_MCX_MCXA_MCXA366.FLEXCAN_WAIT_TIMEOUT (*C macro*), 332
drivers_MCX_MCXA_MCXA366.FLEXCAN_WAKE_UP_FLAG (*C macro*), 335
drivers_MCX_MCXA_MCXA366.flexcan_wake_up_source_t (*C type*), 329
drivers_MCX_MCXA_MCXA366.FLEXCAN_WriteFDTxMb (*C function*), 306
drivers_MCX_MCXA_MCXA366.FLEXCAN_WriteTxMb (*C function*), 306
drivers_MCX_MCXA_MCXA366.flexio_a_format_baud_rate_bps_t (*C type*), 355
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_ClearStatusFlags (*C function*), 358
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_Config_DR_length (*C function*), 356
drivers_MCX_MCXA_MCXA366.flexio_a_format_config_t (*C type*), 356
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_Deinit (*C function*), 357
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_DisableInterrupts (*C function*), 358
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_EnableInterrupts (*C function*), 357
drivers_MCX_MCXA_MCXA366.flexio_a_format_es_t (*C type*), 355

drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_FlushShifters (*C function*), 362
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_GetDefaultConfig (*C function*), 357
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_GetStatusFlags (*C function*), 358
drivers_MCX_MCXA_MCXA366.flexio_a_format_handle_t (*C type*), 356
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_Init (*C function*), 357
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_ReadBlocking (*C function*), 358
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_ReadHalfWord (*C function*), 356
drivers_MCX_MCXA_MCXA366.flexio_a_format_transfer_callback_t (*C type*), 356
drivers_MCX_MCXA_MCXA366.flexio_a_format_transfer_t (*C type*), 356
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_TransferAbortReceive (*C function*), 361
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_TransferAbortSend (*C function*), 360
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_TransferCreateHandle (*C function*), 359
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_TransferGetReceiveCount (*C function*), 361
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_TransferGetSendCount (*C function*), 360
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_TransferHandleIRQ (*C function*), 362
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_TransferReceiveNonBlocking (*C function*), 361
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_TransferSendNonBlocking (*C function*), 360
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_TransferStartRingBuffer (*C function*), 359
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_TransferStopRingBuffer (*C function*), 359
drivers_MCX_MCXA_MCXA366.FLEXIO_A_FORMAT_Type (*C type*), 356
drivers_MCX_MCXA_MCXA366.flexio_a_format_user_modes_t (*C type*), 356
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_WriteBlocking (*C function*), 358
drivers_MCX_MCXA_MCXA366.FLEXIO_A_Format_WriteHalfWord (*C function*), 356
drivers_MCX_MCXA_MCXA366.FLEXIO_CAMERA_ClearStatusFlags (*C function*), 370
drivers_MCX_MCXA_MCXA366.flexio_camera_config_t (*C type*), 371
drivers_MCX_MCXA_MCXA366.FLEXIO_CAMERA_Deinit (*C function*), 369
drivers_MCX_MCXA_MCXA366.FLEXIO_CAMERA_DisableInterrupt (*C function*), 370
drivers_MCX_MCXA_MCXA366.FLEXIO_CAMERA_Enable (*C function*), 370
drivers_MCX_MCXA_MCXA366.FLEXIO_CAMERA_EnableInterrupt (*C function*), 370
drivers_MCX_MCXA_MCXA366.FLEXIO_CAMERA_EnableRxDMA (*C function*), 370
drivers_MCX_MCXA_MCXA366.FLEXIO_CAMERA_GetDefaultConfig (*C function*), 369
drivers_MCX_MCXA_MCXA366.FLEXIO_CAMERA_GetRxBufferAddress (*C function*), 371
drivers_MCX_MCXA_MCXA366.FLEXIO_CAMERA_GetStatusFlags (*C function*), 370
drivers_MCX_MCXA_MCXA366.FLEXIO_CAMERA_Init (*C function*), 369
drivers_MCX_MCXA_MCXA366.FLEXIO_CAMERA_PARALLEL_DATA_WIDTH (*C macro*), 372
drivers_MCX_MCXA_MCXA366.flexio_camera_transfer_t (*C type*), 371
drivers_MCX_MCXA_MCXA366.FLEXIO_CAMERA_Type (*C type*), 371
drivers_MCX_MCXA_MCXA366.FLEXIO_ClearPortOutput (*C function*), 379
drivers_MCX_MCXA_MCXA366.FLEXIO_ClearPortStatus (*C function*), 381
drivers_MCX_MCXA_MCXA366.FLEXIO_ClearShifterErrorFlags (*C function*), 377
drivers_MCX_MCXA_MCXA366.FLEXIO_ClearShifterStatusFlags (*C function*), 377
drivers_MCX_MCXA_MCXA366.FLEXIO_ClearTimerStatusFlags (*C function*), 378
drivers_MCX_MCXA_MCXA366.flexio_config_t (*C type*), 389
drivers_MCX_MCXA_MCXA366.FLEXIO_ConfigPinOverride (*C function*), 380
drivers_MCX_MCXA_MCXA366.FLEXIO_Deinit (*C function*), 373
drivers_MCX_MCXA_MCXA366.FLEXIO_DisableShifterErrorInterrupts (*C function*), 376
drivers_MCX_MCXA_MCXA366.FLEXIO_DisableShifterStatusInterrupts (*C function*), 376
drivers_MCX_MCXA_MCXA366.FLEXIO_DisableTimerStatusInterrupts (*C function*), 377
drivers_MCX_MCXA_MCXA366.FLEXIO_Enable (*C function*), 374
drivers_MCX_MCXA_MCXA366.FLEXIO_EnablePinOutput (*C function*), 380
drivers_MCX_MCXA_MCXA366.FLEXIO_EnableShifterErrorInterrupts (*C function*), 376
drivers_MCX_MCXA_MCXA366.FLEXIO_EnableShifterStatusDMA (*C function*), 378
drivers_MCX_MCXA_MCXA366.FLEXIO_EnableShifterStatusInterrupts (*C function*), 375
drivers_MCX_MCXA_MCXA366.FLEXIO_EnableTimerStatusInterrupts (*C function*), 376
drivers_MCX_MCXA_MCXA366.FLEXIO_GetDefaultConfig (*C function*), 373
drivers_MCX_MCXA_MCXA366.FLEXIO_GetInstance (*C function*), 374

drivers_MCX_MCXA_MCXA366.FLEXIO_GetPinOverride (*C function*), 380
drivers_MCX_MCXA_MCXA366.FLEXIO_GetPinStatus (*C function*), 380
drivers_MCX_MCXA_MCXA366.FLEXIO_GetShifterBufferAddress (*C function*), 378
drivers_MCX_MCXA_MCXA366.FLEXIO_GetShifterErrorFlags (*C function*), 377
drivers_MCX_MCXA_MCXA366.FLEXIO_GetShifterState (*C function*), 374
drivers_MCX_MCXA_MCXA366.FLEXIO_GetShifterStatusFlags (*C function*), 377
drivers_MCX_MCXA_MCXA366.FLEXIO_GetTimerStatusFlags (*C function*), 378
drivers_MCX_MCXA_MCXA366.flexio_gpio_config_t (*C type*), 389
drivers_MCX_MCXA_MCXA366.flexio_gpio_direction_t (*C type*), 389
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_CheckForBusyBus (*C function*), 406
drivers_MCX_MCXA_MCXA366.flexio_i2c_direction_t (*C type*), 413
drivers_MCX_MCXA_MCXA366.flexio_i2c_master_config_t (*C type*), 413
drivers_MCX_MCXA_MCXA366.flexio_i2c_master_handle_t (*C type*), 413
drivers_MCX_MCXA_MCXA366.flexio_i2c_master_transfer_callback_t (*C type*), 413
drivers_MCX_MCXA_MCXA366.flexio_i2c_master_transfer_t (*C type*), 413
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterAbortStop (*C function*), 408
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterClearStatusFlags (*C function*), 407
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterDeinit (*C function*), 406
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterDisableInterrupts (*C function*), 407
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterEnable (*C function*), 407
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterEnableAck (*C function*), 408
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterEnableInterrupts (*C function*), 407
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterGetDefaultConfig (*C function*), 407
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterGetStatusFlags (*C function*), 407
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterInit (*C function*), 406
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterReadBlocking (*C function*), 410
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterReadByte (*C function*), 409
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterRepeatedStart (*C function*), 408
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterSetBaudRate (*C function*), 408
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterSetTransferCount (*C function*), 409
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterStart (*C function*), 408
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterStop (*C function*), 408
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterTransferAbort (*C function*), 411
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterTransferBlocking (*C function*), 410
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterTransferCreateHandle (*C function*), 410
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterTransferGetCount (*C function*), 411
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterTransferHandleIRQ (*C function*), 412
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterTransferNonBlocking (*C function*), 411
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterWriteBlocking (*C function*), 409
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_MasterWriteByte (*C function*), 409
drivers_MCX_MCXA_MCXA366.FLEXIO_I2C_Type (*C type*), 413
drivers_MCX_MCXA_MCXA366.flexio_i2s_callback_t (*C type*), 424
drivers_MCX_MCXA_MCXA366.flexio_i2s_config_t (*C type*), 424
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_Deinit (*C function*), 416
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_DisableInterrupts (*C function*), 417
drivers_MCX_MCXA_MCXA366.flexio_i2s_edma_callback_t (*C type*), 396
drivers_MCX_MCXA_MCXA366.flexio_i2s_edma_handle_t (*C type*), 395
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_Enable (*C function*), 416
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_EnableInterrupts (*C function*), 416
drivers_MCX_MCXA_MCXA366.flexio_i2s_format_t (*C type*), 424
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_GetDefaultConfig (*C function*), 416
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_GetStatusFlags (*C function*), 416
drivers_MCX_MCXA_MCXA366.flexio_i2s_handle_t (*C type*), 424
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_Init (*C function*), 415
drivers_MCX_MCXA_MCXA366.flexio_i2s_master_slave_t (*C type*), 424
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_MasterSetFormat (*C function*), 417
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_ReadBlocking (*C function*), 418
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_ReadData (*C function*), 419

drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_RxEnableDMA (*C function*), 417
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_RxGetDataRegisterAddress (*C function*), 417
drivers_MCX_MCXA_MCXA366.flexio_i2s_sample_rate_t (*C type*), 424
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_SlaveSetFormat (*C function*), 417
drivers_MCX_MCXA_MCXA366.flexio_i2s_transfer_t (*C type*), 424
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferAbortReceive (*C function*), 421
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferAbortReceiveEDMA (*C function*), 395
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferAbortSend (*C function*), 420
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferAbortSendEDMA (*C function*), 395
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferGetReceiveCount (*C function*), 421
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferGetReceiveCountEDMA (*C function*), 395
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferGetSendCount (*C function*), 421
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferGetSendCountEDMA (*C function*), 395
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferReceiveEDMA (*C function*), 394
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferReceiveNonBlocking (*C function*), 420
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferRxCreateHandle (*C function*), 419
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferRxCreateHandleEDMA (*C function*), 393
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferRxHandleIRQ (*C function*), 422
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferSendEDMA (*C function*), 394
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferSendNonBlocking (*C function*), 419
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferSetFormat (*C function*), 419
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferSetFormatEDMA (*C function*), 394
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferTxCreateHandle (*C function*), 419
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferTxCreateHandleEDMA (*C function*), 393
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TransferTxHandleIRQ (*C function*), 421
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TxEnableDMA (*C function*), 417
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_TxGetDataRegisterAddress (*C function*), 417
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_Type (*C type*), 424
drivers_MCX_MCXA_MCXA366.flexio_i2s_word_width_t (*C type*), 424
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_WriteBlocking (*C function*), 418
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_WriteData (*C function*), 418
drivers_MCX_MCXA_MCXA366.FLEXIO_I2S_XFER_QUEUE_SIZE (*C macro*), 424
drivers_MCX_MCXA_MCXA366.FLEXIO_Init (*C function*), 373
drivers_MCX_MCXA_MCXA366.flexio_isr_t (*C type*), 389
drivers_MCX_MCXA_MCXA366.flexio_mculcd_bus_t (*C type*), 437
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_ClearMultiBeatsReadConfig (*C function*), 431
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_ClearMultiBeatsWriteConfig (*C function*), 431
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_ClearSingleBeatReadConfig (*C function*), 430
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_ClearSingleBeatWriteConfig (*C function*), 430
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_ClearStatusFlags (*C function*), 428
drivers_MCX_MCXA_MCXA366.flexio_mculcd_config_t (*C type*), 437
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_DATA_BUS_WIDTH (*C macro*), 437
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_Deinit (*C function*), 427
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_DisableInterrupts (*C function*), 428
drivers_MCX_MCXA_MCXA366.flexio_mculcd_edma_handle_t (*C type*), 398
drivers_MCX_MCXA_MCXA366.flexio_mculcd_edma_transfer_callback_t (*C type*), 398
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_Enable (*C function*), 431
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_EnableInterrupts (*C function*), 428
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_EnableRxDMA (*C function*), 429
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_EnableTxDMA (*C function*), 428
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_GetDefaultConfig (*C function*), 428
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_GetRxDataRegisterAddress (*C function*), 429
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_GetStatusFlags (*C function*), 428
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_GetTxDataRegisterAddress (*C function*), 429
drivers_MCX_MCXA_MCXA366.flexio_mculcd_handle_t (*C type*), 437

drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_Init (*C function*), 427
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_LEGACY_GPIO_FUNC (*C macro*), 437
drivers_MCX_MCXA_MCXA366.flexio_mculcd_pin_func_t (*C type*), 437
drivers_MCX_MCXA_MCXA366.flexio_mculcd_pixel_format_t (*C type*), 436
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_ReadData (*C function*), 431
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_ReadDataArrayBlocking (*C function*), 433
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_SetBaudRate (*C function*), 429
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_SetMultiBeatsReadConfig (*C function*), 431
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_SetMultiBeatsWriteConfig (*C function*), 430
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_SetSingleBeatReadConfig (*C function*), 430
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_SetSingleBeatWriteConfig (*C function*), 429
drivers_MCX_MCXA_MCXA366.flexio_mculcd_smartdma_config_t (*C type*), 441
drivers_MCX_MCXA_MCXA366.flexio_mculcd_smartdma_handle_t (*C type*), 441
drivers_MCX_MCXA_MCXA366.flexio_mculcd_smartdma_transfer_callback_t (*C type*), 441
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_SMARTDMA_TX_ADDR_ALIGN (*C macro*), 441
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_SMARTDMA_TX_LEN_ALIGN (*C macro*), 441
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_StartTransfer (*C function*), 432
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_StopTransfer (*C function*), 432
drivers_MCX_MCXA_MCXA366.flexio_mculcd_transfer_callback_t (*C type*), 437
drivers_MCX_MCXA_MCXA366.flexio_mculcd_transfer_mode_t (*C type*), 437
drivers_MCX_MCXA_MCXA366.flexio_mculcd_transfer_t (*C type*), 437
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_TransferAbort (*C function*), 434
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_TransferAbortEDMA (*C function*), 397
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_TransferAbortSMARTDMA (*C function*), 441
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_TransferBlocking (*C function*), 433
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_TransferCreateHandle (*C function*), 433
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_TransferCreateHandleEDMA (*C function*), 397
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_TransferCreateHandleSMARTDMA (*C function*), 440
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_TransferEDMA (*C function*), 397
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_TransferGetCount (*C function*), 434
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_TransferGetCountEDMA (*C function*), 398
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_TransferGetCountSMARTDMA (*C function*), 441
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_TransferHandleIRQ (*C function*), 435
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_TransferNonBlocking (*C function*), 434
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_TransferSMARTDMA (*C function*), 440
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_Type (*C type*), 437
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_WAIT_COMPLETE_TIME (*C macro*), 437
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_WaitTransmitComplete (*C function*), 432
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_WriteCommandBlocking (*C function*), 432
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_WriteData (*C function*), 432
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_WriteDataArrayBlocking (*C function*), 433
drivers_MCX_MCXA_MCXA366.FLEXIO_MCULCD_WriteSameValueBlocking (*C function*), 433
drivers_MCX_MCXA_MCXA366.flexio_pin_config_t (*C type*), 388
drivers_MCX_MCXA_MCXA366.flexio_pin_input_config_t (*C type*), 389
drivers_MCX_MCXA_MCXA366.flexio_pin_polarity_t (*C type*), 388
drivers_MCX_MCXA_MCXA366.FLEXIO_PinRead (*C function*), 380
drivers_MCX_MCXA_MCXA366.FLEXIO_PinWrite (*C function*), 379
drivers_MCX_MCXA_MCXA366.FLEXIO_ReadPinInput (*C function*), 374
drivers_MCX_MCXA_MCXA366.FLEXIO_RegisterHandleIRQ (*C function*), 379
drivers_MCX_MCXA_MCXA366.FLEXIO_Reset (*C function*), 374
drivers_MCX_MCXA_MCXA366.FLEXIO_SetClockMode (*C function*), 375
drivers_MCX_MCXA_MCXA366.FLEXIO_SetPinConfig (*C function*), 390

drivers_MCX_MCXA_MCXA366.FLEXIO_SetPinLevel (*C function*), 380
drivers_MCX_MCXA_MCXA366.FLEXIO_SetPortOutput (*C function*), 379
drivers_MCX_MCXA_MCXA366.FLEXIO_SetShifterConfig (*C function*), 374
drivers_MCX_MCXA_MCXA366.FLEXIO_SetTimerConfig (*C function*), 375
drivers_MCX_MCXA_MCXA366.flexio_shifter_buffer_type_t (*C type*), 389
drivers_MCX_MCXA_MCXA366.flexio_shifter_config_t (*C type*), 389
drivers_MCX_MCXA_MCXA366.flexio_shifter_input_source_t (*C type*), 389
drivers_MCX_MCXA_MCXA366.flexio_shifter_mode_t (*C type*), 389
drivers_MCX_MCXA_MCXA366.flexio_shifter_start_bit_t (*C type*), 389
drivers_MCX_MCXA_MCXA366.flexio_shifter_stop_bit_t (*C type*), 389
drivers_MCX_MCXA_MCXA366.flexio_shifter_timer_polarity_t (*C type*), 389
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_ClearStatusFlags (*C function*), 445
drivers_MCX_MCXA_MCXA366.flexio_spi_clock_phase_t (*C type*), 453
drivers_MCX_MCXA_MCXA366.flexio_spi_data_bitcount_mode_t (*C type*), 453
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_DisableInterrupts (*C function*), 445
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_DUMMYDATA (*C macro*), 454
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_Enable (*C function*), 446
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_EnableDMA (*C function*), 446
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_EnableInterrupts (*C function*), 445
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_FlushShifters (*C function*), 448
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_GetRxDataRegisterAddress (*C function*), 446
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_GetStatusFlags (*C function*), 445
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_GetTxDataRegisterAddress (*C function*), 446
drivers_MCX_MCXA_MCXA366.flexio_spi_master_config_t (*C type*), 454
drivers_MCX_MCXA_MCXA366.flexio_spi_master_edma_handle_t (*C type*), 402
drivers_MCX_MCXA_MCXA366.flexio_spi_master_edma_transfer_callback_t (*C type*), 402
drivers_MCX_MCXA_MCXA366.flexio_spi_master_handle_t (*C type*), 454
drivers_MCX_MCXA_MCXA366.flexio_spi_master_transfer_callback_t (*C type*), 454
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_MasterDeinit (*C function*), 444
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_MasterGetDefaultConfig (*C function*), 444
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_MasterInit (*C function*), 443
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_MasterSetBaudRate (*C function*), 446
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_MasterTransferAbort (*C function*), 449
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_MasterTransferAbortEDMA (*C function*), 400
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_MasterTransferBlocking (*C function*), 448
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_MasterTransferCreateHandle (*C function*), 448
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_MasterTransferCreateHandleEDMA (*C function*), 399
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_MasterTransferEDMA (*C function*), 400
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_MasterTransferGetCount (*C function*), 449
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_MasterTransferGetCountEDMA (*C function*), 400
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_MasterTransferHandleIRQ (*C function*), 449
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_MasterTransferNonBlocking (*C function*), 449
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_ReadBlocking (*C function*), 448
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_ReadData (*C function*), 447
drivers_MCX_MCXA_MCXA366.flexio_spi_shift_direction_t (*C type*), 453
drivers_MCX_MCXA_MCXA366.flexio_spi_slave_config_t (*C type*), 454
drivers_MCX_MCXA_MCXA366.flexio_spi_slave_edma_handle_t (*C type*), 402
drivers_MCX_MCXA_MCXA366.flexio_spi_slave_edma_transfer_callback_t (*C type*), 402
drivers_MCX_MCXA_MCXA366.flexio_spi_slave_handle_t (*C type*), 454
drivers_MCX_MCXA_MCXA366.flexio_spi_slave_transfer_callback_t (*C type*), 454
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_SlaveDeinit (*C function*), 445
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_SlaveGetDefaultConfig (*C function*), 445
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_SlaveInit (*C function*), 444
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_SlaveTransferAbort (*C function*), 450
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_SlaveTransferAbortEDMA (*C function*), 401
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_SlaveTransferCreateHandle (*C function*), 450
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_SlaveTransferCreateHandleEDMA (*C function*), 401

drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_SlaveTransferEDMA (*C function*), 401
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_SlaveTransferGetCount (*C function*), 450
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_SlaveTransferGetCountEDMA (*C function*), 401
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_SlaveTransferHandleIRQ (*C function*), 451
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_SlaveTransferNonBlocking (*C function*), 450
drivers_MCX_MCXA_MCXA366.flexio_spi_transfer_t (*C type*), 454
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_Type (*C type*), 454
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_WriteBlocking (*C function*), 447
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_WriteData (*C function*), 447
drivers_MCX_MCXA_MCXA366.FLEXIO_SPI_XFER_DATA_FORMAT (*C macro*), 454
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_ClearStatusFlags (*C function*), 462
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_Config_DR_length (*C function*), 460
drivers_MCX_MCXA_MCXA366.flexio_t_format_config_t (*C type*), 459
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_Deinit (*C function*), 461
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_DisableInterrupts (*C function*), 461
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_EnableInterrupts (*C function*), 461
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_GetDefaultConfig (*C function*), 461
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_GetStatusFlags (*C function*), 461
drivers_MCX_MCXA_MCXA366.flexio_t_format_handle_t (*C type*), 459
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_Init (*C function*), 460
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_ReadBlocking (*C function*), 462
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_ReadByte (*C function*), 460
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_SendSyncReq (*C function*), 466
drivers_MCX_MCXA_MCXA366.flexio_t_format_transfer_callback_t (*C type*), 460
drivers_MCX_MCXA_MCXA366.flexio_t_format_transfer_t (*C type*), 459
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_TransferAbortReceive (*C function*), 465
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_TransferAbortSend (*C function*), 464
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_TransferCreateHandle (*C function*), 462
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_TransferGetReceiveCount (*C function*), 465
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_TransferGetSendCount (*C function*), 464
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_TransferReceiveNonBlocking (*C function*), 464
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_TransferSendNonBlocking (*C function*), 463
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_TransferStartRingBuffer (*C function*), 463
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_TransferStopRingBuffer (*C function*), 463
drivers_MCX_MCXA_MCXA366.FLEXIO_T_FORMAT_Type (*C type*), 459
drivers_MCX_MCXA_MCXA366.flexio_t_format_user_modes_t (*C type*), 459
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_WriteBlocking (*C function*), 462
drivers_MCX_MCXA_MCXA366.FLEXIO_T_Format_WriteByte (*C function*), 460
drivers_MCX_MCXA_MCXA366.flexio_timer_config_t (*C type*), 389
drivers_MCX_MCXA_MCXA366.flexio_timer_decrement_source_t (*C type*), 388
drivers_MCX_MCXA_MCXA366.flexio_timer_disable_condition_t (*C type*), 388
drivers_MCX_MCXA_MCXA366.flexio_timer_enable_condition_t (*C type*), 388
drivers_MCX_MCXA_MCXA366.flexio_timer_mode_t (*C type*), 388
drivers_MCX_MCXA_MCXA366.flexio_timer_output_state_t (*C type*), 388
drivers_MCX_MCXA_MCXA366.flexio_timer_output_t (*C type*), 388
drivers_MCX_MCXA_MCXA366.flexio_timer_reset_condition_t (*C type*), 388
drivers_MCX_MCXA_MCXA366.flexio_timer_start_bit_condition_t (*C type*), 388
drivers_MCX_MCXA_MCXA366.flexio_timer_stop_bit_condition_t (*C type*), 388
drivers_MCX_MCXA_MCXA366.flexio_timer_trigger_polarity_t (*C type*), 388
drivers_MCX_MCXA_MCXA366.FLEXIO_TIMER_TRIGGER_SEL_PININPUT (*C macro*), 390
drivers_MCX_MCXA_MCXA366.FLEXIO_TIMER_TRIGGER_SEL_SHIFTnSTAT (*C macro*), 390
drivers_MCX_MCXA_MCXA366.FLEXIO_TIMER_TRIGGER_SEL_TIMn (*C macro*), 390
drivers_MCX_MCXA_MCXA366.flexio_timer_trigger_source_t (*C type*), 388
drivers_MCX_MCXA_MCXA366.FLEXIO_TogglePortOutput (*C function*), 379
drivers_MCX_MCXA_MCXA366.flexio_uart_bit_count_per_char_t (*C type*), 479
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_ClearStatusFlags (*C function*), 472

drivers_MCX_MCXA_MCXA366.flexio_uart_config_t (*C type*), 479
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_Deinit (*C function*), 471
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_DisableInterrupts (*C function*), 472
drivers_MCX_MCXA_MCXA366.flexio_uart_edma_handle_t (*C type*), 405
drivers_MCX_MCXA_MCXA366.flexio_uart_edma_transfer_callback_t (*C type*), 405
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_Enable (*C function*), 473
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_EnableInterrupts (*C function*), 472
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_EnableRxDMA (*C function*), 473
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_EnableTxDMA (*C function*), 473
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_FlushShifters (*C function*), 478
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_GetDefaultConfig (*C function*), 472
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_GetRxDataRegisterAddress (*C function*), 473
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_GetStatusFlags (*C function*), 472
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_GetTxDataRegisterAddress (*C function*), 472
drivers_MCX_MCXA_MCXA366.flexio_uart_handle_t (*C type*), 480
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_Init (*C function*), 471
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_ReadBlocking (*C function*), 474
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_ReadByte (*C function*), 473
drivers_MCX_MCXA_MCXA366.flexio_uart_transfer_callback_t (*C type*), 480
drivers_MCX_MCXA_MCXA366.flexio_uart_transfer_t (*C type*), 479
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_TransferAbortReceive (*C function*), 477
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_TransferAbortReceiveEDMA (*C function*), 404
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_TransferAbortSend (*C function*), 476
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_TransferAbortSendEDMA (*C function*), 404
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_TransferCreateHandle (*C function*), 474
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_TransferCreateHandleEDMA (*C function*), 403
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_TransferGetReceiveCount (*C function*), 477
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_TransferGetReceiveCountEDMA (*C function*), 404
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_TransferGetSendCount (*C function*), 476
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_TransferGetSendCountEDMA (*C function*), 404
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_TransferHandleIRQ (*C function*), 478
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_TransferReceiveEDMA (*C function*), 403
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_TransferReceiveNonBlocking (*C function*), 477
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_TransferSendEDMA (*C function*), 403
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_TransferSendNonBlocking (*C function*), 476
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_TransferStartRingBuffer (*C function*), 475
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_TransferStopRingBuffer (*C function*), 475
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_Type (*C type*), 479
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_WriteBlocking (*C function*), 474
drivers_MCX_MCXA_MCXA366.FLEXIO_UART_WriteByte (*C function*), 473
drivers_MCX_MCXA_MCXA366.FLEXIO_UnregisterHandleIRQ (*C function*), 379
drivers_MCX_MCXA_MCXA366.flexioBase (*C var*), 366, 468
drivers_MCX_MCXA_MCXA366.flexioMcuLcdParam (*C var*), 915
drivers_MCX_MCXA_MCXA366.flexpwm_capture_channel_config_t (*C type*), 529
drivers_MCX_MCXA_MCXA366.flexpwm_capture_channel_t (*C type*), 529
drivers_MCX_MCXA_MCXA366.flexpwm_capture_edge_t (*C type*), 529
drivers_MCX_MCXA_MCXA366.flexpwm_capture_fifo_watermark_t (*C type*), 529
drivers_MCX_MCXA_MCXA366.flexpwm_capture_filter_channel_config_t (*C type*), 530
drivers_MCX_MCXA_MCXA366.flexpwm_capture_filter_config_t (*C type*), 530
drivers_MCX_MCXA_MCXA366.flexpwm_capture_index_t (*C type*), 529
drivers_MCX_MCXA_MCXA366.flexpwm_capture_input_select_t (*C type*), 529
drivers_MCX_MCXA_MCXA366.FLEXPWM_ClearFaultStatusFlags (*C function*), 510
drivers_MCX_MCXA_MCXA366.FLEXPWM_ClearLoadOkay (*C function*), 503
drivers_MCX_MCXA_MCXA366.FLEXPWM_ClearSubmoduleStatusFlags (*C function*), 508
drivers_MCX_MCXA_MCXA366.flexpwm_clock_source_t (*C type*), 525
drivers_MCX_MCXA_MCXA366.flexpwm_compare_mode_t (*C type*), 525
drivers_MCX_MCXA_MCXA366.FLEXPWM_ConfigDMA (*C function*), 511

drivers_MCX_MCXA_MCXA366.FLEXPWM_ConfigFaultFilter (*C function*), 489
drivers_MCX_MCXA_MCXA366.FLEXPWM_ConfigFaultProtection (*C function*), 487
drivers_MCX_MCXA_MCXA366.FLEXPWM_ConfigFaultSubmodule (*C function*), 488
drivers_MCX_MCXA_MCXA366.FLEXPWM_ConfigForceOut (*C function*), 485
drivers_MCX_MCXA_MCXA366.FLEXPWM_ConfigInputCapture (*C function*), 491
drivers_MCX_MCXA_MCXA366.FLEXPWM_ConfigInputCaptureFilter (*C function*), 492
drivers_MCX_MCXA_MCXA366.FLEXPWM_ConfigOutputTrigger (*C function*), 490
drivers_MCX_MCXA_MCXA366.FLEXPWM_ConfigPWM (*C function*), 484
drivers_MCX_MCXA_MCXA366.FLEXPWM_ConfigPWMChannelX (*C function*), 484
drivers_MCX_MCXA_MCXA366.FLEXPWM_ConfigSubmodule (*C function*), 483
drivers_MCX_MCXA_MCXA366.flexpwm_counter_config_t (*C type*), 526
drivers_MCX_MCXA_MCXA366.FLEXPWM_DeInit (*C function*), 531
drivers_MCX_MCXA_MCXA366.FLEXPWM_DisableDMA (*C function*), 512
drivers_MCX_MCXA_MCXA366.FLEXPWM_DisableFaultInterrupts (*C function*), 509
drivers_MCX_MCXA_MCXA366.FLEXPWM_DisableInputCapture (*C function*), 495
drivers_MCX_MCXA_MCXA366.FLEXPWM_DisablePWMOutput (*C function*), 507
drivers_MCX_MCXA_MCXA366.FLEXPWM_DisableSubmoduleCounter (*C function*), 506
drivers_MCX_MCXA_MCXA366.FLEXPWM_DisableSubmoduleInterrupts (*C function*), 508
drivers_MCX_MCXA_MCXA366.flexpwm_dma_capture_source_t (*C type*), 530
drivers_MCX_MCXA_MCXA366.flexpwm_dma_config_t (*C type*), 530
drivers_MCX_MCXA_MCXA366.FLEXPWM_EnableDMA (*C function*), 511
drivers_MCX_MCXA_MCXA366.FLEXPWM_EnableFaultInterrupts (*C function*), 509
drivers_MCX_MCXA_MCXA366.FLEXPWM_EnableInputCapture (*C function*), 494
drivers_MCX_MCXA_MCXA366.FLEXPWM_EnablePWMOutput (*C function*), 506
drivers_MCX_MCXA_MCXA366.FLEXPWM_EnableSubmoduleCounter (*C function*), 505
drivers_MCX_MCXA_MCXA366.FLEXPWM_EnableSubmoduleInterrupts (*C function*), 508
drivers_MCX_MCXA_MCXA366.FLEXPWM_EnableUpdateMaskImmediately (*C function*), 500
drivers_MCX_MCXA_MCXA366.flexpwm_fault_clearing_mode_t (*C type*), 527
drivers_MCX_MCXA_MCXA366.flexpwm_fault_config_t (*C type*), 527
drivers_MCX_MCXA_MCXA366.flexpwm_fault_filter_config_t (*C type*), 528
drivers_MCX_MCXA_MCXA366.flexpwm_fault_mask_t (*C type*), 527
drivers_MCX_MCXA_MCXA366.flexpwm_fault_output_behavior_t (*C type*), 527
drivers_MCX_MCXA_MCXA366.flexpwm_fault_output_config_t (*C type*), 527
drivers_MCX_MCXA_MCXA366.flexpwm_fault_submodule_config_t (*C type*), 527
drivers_MCX_MCXA_MCXA366.flexpwm_force_out_channel_config_t (*C type*), 527
drivers_MCX_MCXA_MCXA366.flexpwm_force_out_config_t (*C type*), 527
drivers_MCX_MCXA_MCXA366.flexpwm_force_output_source_t (*C type*), 526
drivers_MCX_MCXA_MCXA366.flexpwm_force_pwm_source_t (*C type*), 526
drivers_MCX_MCXA_MCXA366.FLEXPWM_GET_FCTRL2_REG (*C macro*), 531
drivers_MCX_MCXA_MCXA366.FLEXPWM_GET_FCTRL_REG (*C macro*), 531
drivers_MCX_MCXA_MCXA366.FLEXPWM_GET_FFILT_REG (*C macro*), 531
drivers_MCX_MCXA_MCXA366.FLEXPWM_GET_FSTS_REG (*C macro*), 531
drivers_MCX_MCXA_MCXA366.FLEXPWM_GetDefaultCaptureFilterConfig (*C function*), 491
drivers_MCX_MCXA_MCXA366.FLEXPWM_GetDefaultFaultConfig (*C function*), 486
drivers_MCX_MCXA_MCXA366.FLEXPWM_GetDefaultFaultFilterConfig (*C function*), 487
drivers_MCX_MCXA_MCXA366.FLEXPWM_GetDefaultFaultSubmoduleConfig (*C function*), 487
drivers_MCX_MCXA_MCXA366.FLEXPWM_GetDefaultForceOutConfig (*C function*), 485
drivers_MCX_MCXA_MCXA366.FLEXPWM_GetDefaultInputCaptureConfig (*C function*), 491
drivers_MCX_MCXA_MCXA366.FLEXPWM_GetDefaultOutputTriggerConfig (*C function*), 490
drivers_MCX_MCXA_MCXA366.FLEXPWM_GetDefaultSubmoduleConfig (*C function*), 482
drivers_MCX_MCXA_MCXA366.FLEXPWM_GetFaultFilteredPinStatusFlags (*C function*), 510
drivers_MCX_MCXA_MCXA366.FLEXPWM_GetFaultStatusFlags (*C function*), 510
drivers_MCX_MCXA_MCXA366.FLEXPWM_GetInputCaptureCycle (*C function*), 494
drivers_MCX_MCXA_MCXA366.FLEXPWM_GetInputCaptureValue (*C function*), 493
drivers_MCX_MCXA_MCXA366.FLEXPWM_GetInstance (*C function*), 530
drivers_MCX_MCXA_MCXA366.FLEXPWM_GetLoadOkay (*C function*), 504
drivers_MCX_MCXA_MCXA366.FLEXPWM_GetSubmoduleStatusFlags (*C function*), 508
drivers_MCX_MCXA_MCXA366.FLEXPWM_Init (*C function*), 530

drivers_MCX_MCXA_MCXA366.flexpwm_init_source_t (*C type*), 525
drivers_MCX_MCXA_MCXA366.flexpwm_input_capture_config_t (*C type*), 529
drivers_MCX_MCXA_MCXA366.flexpwm_ipol_source_t (*C type*), 526
drivers_MCX_MCXA_MCXA366.flexpwm_load_mode_t (*C type*), 525
drivers_MCX_MCXA_MCXA366.FLEXPWM_MaskPWMOutput (*C function*), 499
drivers_MCX_MCXA_MCXA366.flexpwm_output_trigger_config_t (*C type*), 528
drivers_MCX_MCXA_MCXA366.flexpwm_output_trigger_mask_t (*C type*), 528
drivers_MCX_MCXA_MCXA366.flexpwm_prescaler_t (*C type*), 525
drivers_MCX_MCXA_MCXA366.flexpwm_pwm_channel_config_t (*C type*), 526
drivers_MCX_MCXA_MCXA366.flexpwm_pwm_config_t (*C type*), 526
drivers_MCX_MCXA_MCXA366.flexpwm_pwm_polarity_t (*C type*), 526
drivers_MCX_MCXA_MCXA366.flexpwm_reload_config_t (*C type*), 526
drivers_MCX_MCXA_MCXA366.flexpwm_reload_source_t (*C type*), 525
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetCompareMode (*C function*), 498
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetComplementaryPWMSource23 (*C function*), 502
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetComplementaryPWMSource45 (*C function*), 502
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetCounterForceInitialization (*C function*), 505
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetDTCNT0 (*C function*), 497
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetDTCNT1 (*C function*), 498
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetINIT (*C function*), 495
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetLoadOkay (*C function*), 503
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetLocalForceOut (*C function*), 504
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetPhaseDelay (*C function*), 498
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetPWMSource23 (*C function*), 500
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetPWMSource45 (*C function*), 501
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetSoftwareControlOutput23 (*C function*), 501
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetSoftwareControlOutput45 (*C function*), 501
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetVAL0 (*C function*), 495
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetVAL1 (*C function*), 496
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetVAL2 (*C function*), 496
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetVAL3 (*C function*), 496
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetVAL4 (*C function*), 497
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetVAL5 (*C function*), 497
drivers_MCX_MCXA_MCXA366.FLEXPWM_SetWriteProtection (*C function*), 507
drivers_MCX_MCXA_MCXA366.flexpwm_stretch_prescaler_t (*C type*), 528
drivers_MCX_MCXA_MCXA366.flexpwm_submodule_config_t (*C type*), 526
drivers_MCX_MCXA_MCXA366.flexpwm_submodule_mask_t (*C type*), 525
drivers_MCX_MCXA_MCXA366.flexpwm_trigger_frequency_t (*C type*), 528
drivers_MCX_MCXA_MCXA366.flexpwm_trigger_mux_source_t (*C type*), 528
drivers_MCX_MCXA_MCXA366.FLEXPWM_UnMaskPWMOutput (*C function*), 499
drivers_MCX_MCXA_MCXA366.flexpwm_write_protect_t (*C type*), 528
drivers_MCX_MCXA_MCXA366.freq_measure_config_t (*C type*), 657
drivers_MCX_MCXA_MCXA366.FREQME_CalculateTargetClkFreq (*C function*), 654
drivers_MCX_MCXA_MCXA366.FREQME_CheckContinuousMode (*C function*), 653
drivers_MCX_MCXA_MCXA366.FREQME_CheckOperateMode (*C function*), 654
drivers_MCX_MCXA_MCXA366.FREQME_CheckPulsePolarity (*C function*), 655
drivers_MCX_MCXA_MCXA366.FREQME_ClearInterruptStatusFlags (*C function*), 655
drivers_MCX_MCXA_MCXA366.FREQME_DisableInterrupts (*C function*), 656
drivers_MCX_MCXA_MCXA366.FREQME_EnableContinuousMode (*C function*), 653
drivers_MCX_MCXA_MCXA366.FREQME_EnableInterrupts (*C function*), 656
drivers_MCX_MCXA_MCXA366.FREQME_GetDefaultConfig (*C function*), 653
drivers_MCX_MCXA_MCXA366.FREQME_GetInterruptStatusFlags (*C function*), 655
drivers_MCX_MCXA_MCXA366.FREQME_GetMeasurementResult (*C function*), 655
drivers_MCX_MCXA_MCXA366.FREQME_GetReferenceClkScaleValue (*C function*), 655
drivers_MCX_MCXA_MCXA366.FREQME_Init (*C function*), 652
drivers_MCX_MCXA_MCXA366.freqme_mode_attribute_t (*C type*), 657
drivers_MCX_MCXA_MCXA366.freqme_operate_mode_t (*C type*), 657
drivers_MCX_MCXA_MCXA366.freqme_pulse_polarity_t (*C type*), 657

drivers_MCX_MCXA_MCXA366.FREQME_SetMaxExpectedValue (*C function*), 654
drivers_MCX_MCXA_MCXA366.FREQME_SetMinExpectedValue (*C function*), 654
drivers_MCX_MCXA_MCXA366.FREQME_SetOperateMode (*C function*), 653
drivers_MCX_MCXA_MCXA366.FREQME_SetPulsePolarity (*C function*), 655
drivers_MCX_MCXA_MCXA366.FREQME_SetReferenceClk (*C function*), 654
drivers_MCX_MCXA_MCXA366.FREQME_SetTargetClk (*C function*), 654
drivers_MCX_MCXA_MCXA366.FREQME_StartMeasurementCycle (*C function*), 653
drivers_MCX_MCXA_MCXA366.FREQME_TerminateMeasurementCycle (*C function*), 653
drivers_MCX_MCXA_MCXA366.FSL_AOI_DRIVER_VERSION (*C macro*), 202
drivers_MCX_MCXA_MCXA366.FSL_CACHE_LPCAC_DRIVER_VERSION (*C macro*), 205
drivers_MCX_MCXA_MCXA366.FSL_CDOG_DRIVER_VERSION (*C macro*), 208
drivers_MCX_MCXA_MCXA366.FSL_CMC_DRIVER_VERSION (*C macro*), 774
drivers_MCX_MCXA_MCXA366.FSL_COMMON_DRIVER_VERSION (*C macro*), 614
drivers_MCX_MCXA_MCXA366.FSL_COMPONENT_ID (*C macro*), 860
drivers_MCX_MCXA_MCXA366.FSL_CRC_DRIVER_VERSION (*C macro*), 209
drivers_MCX_MCXA_MCXA366.FSL_CTIMER_DRIVER_VERSION (*C macro*), 215
drivers_MCX_MCXA_MCXA366.FSL_DAC_DRIVER_VERSION (*C macro*), 225
drivers_MCX_MCXA_MCXA366.FSL_DRIVER_TRANSFER_DOUBLE_WEAK_IRQ (*C macro*), 630
drivers_MCX_MCXA_MCXA366.FSL_EDMA_DRIVER_EDMA4 (*C macro*), 258
drivers_MCX_MCXA_MCXA366.FSL_EDMA_DRIVER_UNIFIED (*C macro*), 258
drivers_MCX_MCXA_MCXA366.FSL_EDMA_DRIVER_VERSION (*C macro*), 249
drivers_MCX_MCXA_MCXA366.FSL_EIM_DRIVER_VERSION (*C macro*), 273
drivers_MCX_MCXA_MCXA366.FSL_EQDC_DRIVER_VERSION (*C macro*), 290
drivers_MCX_MCXA_MCXA366.FSL_ERM_DRIVER_VERSION (*C macro*), 294
drivers_MCX_MCXA_MCXA366.FSL_FLEXCAN_DRIVER_VERSION (*C macro*), 316
drivers_MCX_MCXA_MCXA366.FSL_FLEXCAN_EDMA_DRIVER_VERSION (*C macro*), 352
drivers_MCX_MCXA_MCXA366.FSL_FLEXIO_A_FORMAT_DRIVER_VERSION (*C macro*), 366
drivers_MCX_MCXA_MCXA366.FSL_FLEXIO_CAMERA_DRIVER_VERSION (*C macro*), 371
drivers_MCX_MCXA_MCXA366.FSL_FLEXIO_DRIVER_VERSION (*C macro*), 381
drivers_MCX_MCXA_MCXA366.FSL_FLEXIO_I2C_MASTER_DRIVER_VERSION (*C macro*), 412
drivers_MCX_MCXA_MCXA366.FSL_FLEXIO_I2S_DRIVER_VERSION (*C macro*), 422
drivers_MCX_MCXA_MCXA366.FSL_FLEXIO_I2S_EDMA_DRIVER_VERSION (*C macro*), 395
drivers_MCX_MCXA_MCXA366.FSL_FLEXIO_MCULCD_DRIVER_VERSION (*C macro*), 435
drivers_MCX_MCXA_MCXA366.FSL_FLEXIO_MCULCD_EDMA_DRIVER_VERSION (*C macro*), 398
drivers_MCX_MCXA_MCXA366.FSL_FLEXIO_MCULCD_SMARTDMA_DRIVER_VERSION (*C macro*), 441
drivers_MCX_MCXA_MCXA366.FSL_FLEXIO_SPI_DRIVER_VERSION (*C macro*), 451
drivers_MCX_MCXA_MCXA366.FSL_FLEXIO_SPI_EDMA_DRIVER_VERSION (*C macro*), 402
drivers_MCX_MCXA_MCXA366.FSL_FLEXIO_T_FORMAT_DRIVER_VERSION (*C macro*), 468
drivers_MCX_MCXA_MCXA366.FSL_FLEXIO_UART_DRIVER_VERSION (*C macro*), 478
drivers_MCX_MCXA_MCXA366.FSL_FLEXIO_UART_EDMA_DRIVER_VERSION (*C macro*), 405
drivers_MCX_MCXA_MCXA366.FSL_FLEXPWM_DRIVER_VERSION (*C macro*), 512
drivers_MCX_MCXA_MCXA366.FSL_FREQME_DRIVER_VERSION (*C macro*), 656
drivers_MCX_MCXA_MCXA366.FSL_GLIKEY_DRIVER_VERSION (*C macro*), 542
drivers_MCX_MCXA_MCXA366.FSL_GPIO_DRIVER_VERSION (*C macro*), 546
drivers_MCX_MCXA_MCXA366.FSL_I3C_DRIVER_VERSION (*C macro*), 556
drivers_MCX_MCXA_MCXA366.FSL_INPUTMUX_DRIVER_VERSION (*C macro*), 613
drivers_MCX_MCXA_MCXA366.FSL_LPADC_DRIVER_VERSION (*C macro*), 649
drivers_MCX_MCXA_MCXA366.FSL_LPCMP_DRIVER_VERSION (*C macro*), 662
drivers_MCX_MCXA_MCXA366.FSL_LPI2C_DRIVER_VERSION (*C macro*), 670
drivers_MCX_MCXA_MCXA366.FSL_LPSPI_DRIVER_VERSION (*C macro*), 711
drivers_MCX_MCXA_MCXA366.FSL_LPSPI_EDMA_DRIVER_VERSION (*C macro*), 725

drivers_MCX_MCXA_MCXA366.FSL_LPTMR_DRIVER_VERSION (*C macro*), 735
drivers_MCX_MCXA_MCXA366.FSL_LPUART_DRIVER_VERSION (*C macro*), 750
drivers_MCX_MCXA_MCXA366.FSL_LPUART_EDMA_DRIVER_VERSION (*C macro*), 763
drivers_MCX_MCXA_MCXA366.FSL_MAU_DRIVER_VERSION (*C macro*), 766
drivers_MCX_MCXA_MCXA366.FSL_OPAMP_DRIVER_VERSION (*C macro*), 847
drivers_MCX_MCXA_MCXA366.FSL_OSTIMER_DRIVER_VERSION (*C macro*), 852
drivers_MCX_MCXA_MCXA366.FSL_PORT_DRIVER_VERSION (*C macro*), 856
drivers_MCX_MCXA_MCXA366.FSL_PWM_DRIVER_VERSION (*C macro*), 867
drivers_MCX_MCXA_MCXA366.FSL_RTC_DRIVER_VERSION (*C macro*), 894
drivers_MCX_MCXA_MCXA366.FSL_SLCD_DRIVER_VERSION (*C macro*), 903
drivers_MCX_MCXA_MCXA366.FSL_SMARTDMA_DRIVER_VERSION (*C macro*), 913
drivers_MCX_MCXA_MCXA366.FSL_SMARTDMA_MCXA_DRIVER_VERSION (*C macro*), 915
drivers_MCX_MCXA_MCXA366.FSL_SPC_DRIVER_VERSION (*C macro*), 810
drivers_MCX_MCXA_MCXA366.FSL_TDET_DRIVER_VERSION (*C macro*), 920
drivers_MCX_MCXA_MCXA366.FSL_TRDC_DRIVER_VERSION (*C macro*), 949
drivers_MCX_MCXA_MCXA366.FSL_TRNG_DRIVER_VERSION (*C macro*), 972
drivers_MCX_MCXA_MCXA366.FSL_UTICK_DRIVER_VERSION (*C macro*), 979
drivers_MCX_MCXA_MCXA366.FSL_VBAT_DRIVER_VERSION (*C macro*), 832
drivers_MCX_MCXA_MCXA366.FSL_WAKETIMER_DRIVER_VERSION (*C macro*), 981
drivers_MCX_MCXA_MCXA366.FSL_WUU_DRIVER_VERSION (*C macro*), 984
drivers_MCX_MCXA_MCXA366.FSL_WWDT_DRIVER_VERSION (*C macro*), 990
drivers_MCX_MCXA_MCXA366.g_lpspiDummyData (*C var*), 720
drivers_MCX_MCXA_MCXA366.GET_ENCODER_ID (*C macro*), 366
drivers_MCX_MCXA_MCXA366.GET_TEMPERATURE_DATA (*C macro*), 366
drivers_MCX_MCXA_MCXA366.GET_TEMPERATURE_IS_BELOW_ZERO (*C macro*), 366
drivers_MCX_MCXA_MCXA366.GET_TEMPERATURE_VALUE (*C macro*), 366
drivers_MCX_MCXA_MCXA366.GLIKEY_CheckLock (*C function*), 543
drivers_MCX_MCXA_MCXA366.GLIKEY_ClearIntStatus (*C function*), 544
drivers_MCX_MCXA_MCXA366.GLIKEY_CODEWORD_STEP1 (*C macro*), 542
drivers_MCX_MCXA_MCXA366.GLIKEY_CODEWORD_STEP2 (*C macro*), 542
drivers_MCX_MCXA_MCXA366.GLIKEY_CODEWORD_STEP3 (*C macro*), 542
drivers_MCX_MCXA_MCXA366.GLIKEY_CODEWORD_STEP4 (*C macro*), 542
drivers_MCX_MCXA_MCXA366.GLIKEY_CODEWORD_STEP5 (*C macro*), 542
drivers_MCX_MCXA_MCXA366.GLIKEY_CODEWORD_STEP6 (*C macro*), 542
drivers_MCX_MCXA_MCXA366.GLIKEY_CODEWORD_STEP7 (*C macro*), 542
drivers_MCX_MCXA_MCXA366.GLIKEY_CODEWORD_STEP_EN (*C macro*), 542
drivers_MCX_MCXA_MCXA366.GLIKEY_ContinueEnable (*C function*), 545
drivers_MCX_MCXA_MCXA366.GLIKEY_EndOperation (*C function*), 545
drivers_MCX_MCXA_MCXA366.GLIKEY_FSM_INIT (*C macro*), 542
drivers_MCX_MCXA_MCXA366.GLIKEY_FSM_LOCKED (*C macro*), 543
drivers_MCX_MCXA_MCXA366.GLIKEY_FSM_SSR_RESET (*C macro*), 543
drivers_MCX_MCXA_MCXA366.GLIKEY_FSM_STEP1 (*C macro*), 542
drivers_MCX_MCXA_MCXA366.GLIKEY_FSM_STEP2 (*C macro*), 542
drivers_MCX_MCXA_MCXA366.GLIKEY_FSM_STEP3 (*C macro*), 543
drivers_MCX_MCXA_MCXA366.GLIKEY_FSM_STEP4 (*C macro*), 543
drivers_MCX_MCXA_MCXA366.GLIKEY_FSM_WR_DIS (*C macro*), 542
drivers_MCX_MCXA_MCXA366.GLIKEY_FSM_WR_EN (*C macro*), 543
drivers_MCX_MCXA_MCXA366.GLIKEY_GetIntEnable (*C function*), 544
drivers_MCX_MCXA_MCXA366.GLIKEY_GetStatus (*C function*), 543
drivers_MCX_MCXA_MCXA366.GLIKEY_IsIndexLocked (*C function*), 545
drivers_MCX_MCXA_MCXA366.GLIKEY_IsLocked (*C function*), 543
drivers_MCX_MCXA_MCXA366.GLIKEY_Lock (*C function*), 544
drivers_MCX_MCXA_MCXA366.GLIKEY_LockIndex (*C function*), 544
drivers_MCX_MCXA_MCXA366.GLIKEY_ResetIndex (*C function*), 546
drivers_MCX_MCXA_MCXA366.GLIKEY_SetIntEnable (*C function*), 544
drivers_MCX_MCXA_MCXA366.GLIKEY_SetIntStatus (*C function*), 544
drivers_MCX_MCXA_MCXA366.GLIKEY_StartEnable (*C function*), 545
drivers_MCX_MCXA_MCXA366.GLIKEY_SyncReset (*C function*), 543

drivers_MCX_MCXA_MCXA366.GPIO_CheckAttributeBytes (*C function*), 555
drivers_MCX_MCXA_MCXA366.gpio_checker_attribute_t (*C type*), 549
drivers_MCX_MCXA_MCXA366.GPIO_DisableInterruptControlNonPrivilege (*C function*), 552
drivers_MCX_MCXA_MCXA366.GPIO_DisableInterruptControlNonSecure (*C function*), 551
drivers_MCX_MCXA_MCXA366.GPIO_DisablePinControlNonPrivilege (*C function*), 551
drivers_MCX_MCXA_MCXA366.GPIO_DisablePinControlNonSecure (*C function*), 551
drivers_MCX_MCXA_MCXA366.GPIO_EnableInterruptControlNonPrivilege (*C function*), 551
drivers_MCX_MCXA_MCXA366.GPIO_EnableInterruptControlNonSecure (*C function*), 551
drivers_MCX_MCXA_MCXA366.GPIO_EnablePinControlNonPrivilege (*C function*), 551
drivers_MCX_MCXA_MCXA366.GPIO_EnablePinControlNonSecure (*C function*), 551
drivers_MCX_MCXA_MCXA366.GPIO_FIT_REG (*C macro*), 549
drivers_MCX_MCXA_MCXA366.GPIO_GetVersionInfo (*C function*), 550
drivers_MCX_MCXA_MCXA366.GPIO_GpioClearInterruptChannelFlags (*C function*), 554
drivers_MCX_MCXA_MCXA366.GPIO_GpioClearInterruptFlags (*C function*), 554
drivers_MCX_MCXA_MCXA366.GPIO_GpioGetInterruptChannelFlags (*C function*), 554
drivers_MCX_MCXA_MCXA366.GPIO_GpioGetInterruptFlags (*C function*), 554
drivers_MCX_MCXA_MCXA366.gpio_interrupt_config_t (*C type*), 549
drivers_MCX_MCXA_MCXA366.gpio_interrupt_selection_t (*C type*), 549
drivers_MCX_MCXA_MCXA366.gpio_pin_config_t (*C type*), 549
drivers_MCX_MCXA_MCXA366.gpio_pin_direction_t (*C type*), 549
drivers_MCX_MCXA_MCXA366.gpio_pin_interrupt_control_t (*C enum*), 548
drivers_MCX_MCXA_MCXA366.gpio_pin_interrupt_control_t.kGPIO_InterruptControlNonPrivilege (*C enumerator*), 548
drivers_MCX_MCXA_MCXA366.gpio_pin_interrupt_control_t.kGPIO_InterruptControlNonSecure (*C enumerator*), 548
drivers_MCX_MCXA_MCXA366.gpio_pin_interrupt_control_t.kGPIO_PinControlNonPrivilege (*C enumerator*), 548
drivers_MCX_MCXA_MCXA366.gpio_pin_interrupt_control_t.kGPIO_PinControlNonSecure (*C enumerator*), 548
drivers_MCX_MCXA_MCXA366.GPIO_PinClearInterruptFlag (*C function*), 554
drivers_MCX_MCXA_MCXA366.GPIO_PinGetInterruptFlag (*C function*), 554
drivers_MCX_MCXA_MCXA366.GPIO_PinInit (*C function*), 550
drivers_MCX_MCXA_MCXA366.GPIO_PinRead (*C function*), 552
drivers_MCX_MCXA_MCXA366.GPIO_PinWrite (*C function*), 552
drivers_MCX_MCXA_MCXA366.GPIO_PortClear (*C function*), 552
drivers_MCX_MCXA_MCXA366.GPIO_PortClearInterruptFlags (*C macro*), 555
drivers_MCX_MCXA_MCXA366.GPIO_PortDenit (*C function*), 550
drivers_MCX_MCXA_MCXA366.GPIO_PortGetInterruptFlags (*C macro*), 555
drivers_MCX_MCXA_MCXA366.GPIO_PortInit (*C function*), 550
drivers_MCX_MCXA_MCXA366.GPIO_PortInputDisable (*C function*), 552
drivers_MCX_MCXA_MCXA366.GPIO_PortInputEnable (*C function*), 552
drivers_MCX_MCXA_MCXA366.GPIO_PortSet (*C function*), 552
drivers_MCX_MCXA_MCXA366.GPIO_PortToggle (*C function*), 552
drivers_MCX_MCXA_MCXA366.GPIO_SecurePrivilegeLock (*C function*), 550
drivers_MCX_MCXA_MCXA366.GPIO_SetMultipleInterruptPinsConfig (*C function*), 555
drivers_MCX_MCXA_MCXA366.GPIO_SetPinInterruptChannel (*C function*), 553
drivers_MCX_MCXA_MCXA366.GPIO_SetPinInterruptConfig (*C function*), 553
drivers_MCX_MCXA_MCXA366.gpio_version_info_t (*C type*), 549
drivers_MCX_MCXA_MCXA366.HALFWORD_NUM (*C macro*), 366
drivers_MCX_MCXA_MCXA366.hanlde (*C var*), 366, 468
drivers_MCX_MCXA_MCXA366.I2C_RETRY_TIMES (*C macro*), 413, 671
drivers_MCX_MCXA_MCXA366.I2S_RETRY_TIMES (*C macro*), 424
drivers_MCX_MCXA_MCXA366.i3c_baudrate_hz_t (*C type*), 587
drivers_MCX_MCXA_MCXA366.i3c_bus_request_t (*C type*), 586
drivers_MCX_MCXA_MCXA366.i3c_bus_type_t (*C type*), 586
drivers_MCX_MCXA_MCXA366.I3C_CheckForBusyBus (*C function*), 562
drivers_MCX_MCXA_MCXA366.i3c_config_t (*C type*), 558
drivers_MCX_MCXA_MCXA366.i3c_device_info_t (*C type*), 557

drivers_MCX_MCXA_MCXA366.i3c_direction_t (*C type*), 586
drivers_MCX_MCXA_MCXA366.I3C_DriverIRQHandler (*C function*), 578
drivers_MCX_MCXA_MCXA366.I3C_GetDefaultConfig (*C function*), 558
drivers_MCX_MCXA_MCXA366.I3C_GetIBIAddress (*C function*), 575
drivers_MCX_MCXA_MCXA366.I3C_GetIBIType (*C function*), 575
drivers_MCX_MCXA_MCXA366.I3C_GetInstance (*C function*), 558
drivers_MCX_MCXA_MCXA366.i3c_hdr_mode_t (*C type*), 557
drivers_MCX_MCXA_MCXA366.I3C_IBI_BUFF_SIZE (*C macro*), 557
drivers_MCX_MCXA_MCXA366.i3c_ibi_response_t (*C type*), 586
drivers_MCX_MCXA_MCXA366.i3c_ibi_state_t (*C type*), 586
drivers_MCX_MCXA_MCXA366.i3c_ibi_type_t (*C type*), 586
drivers_MCX_MCXA_MCXA366.I3C_Init (*C function*), 559
drivers_MCX_MCXA_MCXA366.i3c_legacy_i2c_speed_mode_t (*C type*), 587
drivers_MCX_MCXA_MCXA366.i3c_master_baudrate_config_t (*C type*), 587
drivers_MCX_MCXA_MCXA366.i3c_master_bus_mode_t (*C type*), 587
drivers_MCX_MCXA_MCXA366.i3c_master_config_t (*C type*), 587
drivers_MCX_MCXA_MCXA366.i3c_master_daa_baudrate_t (*C type*), 587
drivers_MCX_MCXA_MCXA366.i3c_master_edma_callback_t (*C type*), 594
drivers_MCX_MCXA_MCXA366.i3c_master_edma_handle_t (*C type*), 594
drivers_MCX_MCXA_MCXA366.i3c_master_enable_t (*C type*), 586
drivers_MCX_MCXA_MCXA366.i3c_master_handle_t (*C type*), 588
drivers_MCX_MCXA_MCXA366.i3c_master_hkeep_t (*C type*), 586
drivers_MCX_MCXA_MCXA366.i3c_master_isr_t (*C type*), 588
drivers_MCX_MCXA_MCXA366.i3c_master_src_clk_t (*C type*), 587
drivers_MCX_MCXA_MCXA366.i3c_master_state_t (*C type*), 586
drivers_MCX_MCXA_MCXA366.i3c_master_transfer_callback_t (*C type*), 588
drivers_MCX_MCXA_MCXA366.i3c_master_transfer_t (*C type*), 587
drivers_MCX_MCXA_MCXA366.I3C_MasterCalcTiming (*C function*), 570
drivers_MCX_MCXA_MCXA366.I3C_MasterCheckAndClearError (*C function*), 562
drivers_MCX_MCXA_MCXA366.I3C_MasterClearDeviceCount (*C function*), 576
drivers_MCX_MCXA_MCXA366.I3C_MasterClearErrorStatusFlags (*C function*), 564
drivers_MCX_MCXA_MCXA366.I3C_MasterClearStatusFlags (*C function*), 563
drivers_MCX_MCXA_MCXA366.I3C_MasterDeinit (*C function*), 562
drivers_MCX_MCXA_MCXA366.I3C_MasterDisableInterrupts (*C function*), 566
drivers_MCX_MCXA_MCXA366.I3C_MasterEmitIBIResponse (*C function*), 574
drivers_MCX_MCXA_MCXA366.I3C_MasterEmitRequest (*C function*), 574
drivers_MCX_MCXA_MCXA366.I3C_MasterEnable (*C function*), 562
drivers_MCX_MCXA_MCXA366.I3C_MasterEnableDMA (*C function*), 568
drivers_MCX_MCXA_MCXA366.I3C_MasterEnableInterrupts (*C function*), 566
drivers_MCX_MCXA_MCXA366.I3C_MasterGetBusIdleState (*C function*), 571
drivers_MCX_MCXA_MCXA366.I3C_MasterGetDefaultConfig (*C function*), 561
drivers_MCX_MCXA_MCXA366.I3C_MasterGetDeviceListAfterDAA (*C function*), 576
drivers_MCX_MCXA_MCXA366.I3C_MasterGetEnabledInterrupts (*C function*), 566
drivers_MCX_MCXA_MCXA366.I3C_MasterGetErrorStatusFlags (*C function*), 563
drivers_MCX_MCXA_MCXA366.I3C_MasterGetFifoCounts (*C function*), 569
drivers_MCX_MCXA_MCXA366.I3C_MasterGetI2CPresetTiming (*C function*), 570
drivers_MCX_MCXA_MCXA366.I3C_MasterGetIBIRules (*C function*), 574
drivers_MCX_MCXA_MCXA366.I3C_MasterGetPendingInterrupts (*C function*), 566
drivers_MCX_MCXA_MCXA366.I3C_MasterGetRxFifoAddress (*C function*), 568
drivers_MCX_MCXA_MCXA366.I3C_MasterGetState (*C function*), 564
drivers_MCX_MCXA_MCXA366.I3C_MasterGetStatusFlags (*C function*), 563
drivers_MCX_MCXA_MCXA366.I3C_MasterGetTxFifoAddress (*C function*), 568
drivers_MCX_MCXA_MCXA366.I3C_MasterInit (*C function*), 561
drivers_MCX_MCXA_MCXA366.I3C_MasterProcessDAA (*C function*), 575
drivers_MCX_MCXA_MCXA366.I3C_MasterProcessDAASpecifiedBaudrate (*C function*), 575
drivers_MCX_MCXA_MCXA366.I3C_MasterReceive (*C function*), 573
drivers_MCX_MCXA_MCXA366.I3C_MasterRegisterIBI (*C function*), 574
drivers_MCX_MCXA_MCXA366.I3C_MasterRepeatedStart (*C function*), 572

drivers_MCX_MCXA_MCXA366.I3C_MasterRepeatedStartWithRxSize (*C function*), 572
drivers_MCX_MCXA_MCXA366.I3C_MasterSend (*C function*), 573
drivers_MCX_MCXA_MCXA366.I3C_MasterSetBaudRate (*C function*), 570
drivers_MCX_MCXA_MCXA366.I3C_MasterSetTiming (*C function*), 571
drivers_MCX_MCXA_MCXA366.I3C_MasterSetWatermarks (*C function*), 569
drivers_MCX_MCXA_MCXA366.I3C_MasterStart (*C function*), 571
drivers_MCX_MCXA_MCXA366.I3C_MasterStartWithRxSize (*C function*), 571
drivers_MCX_MCXA_MCXA366.I3C_MasterStop (*C function*), 574
drivers_MCX_MCXA_MCXA366.I3C_MasterTransferAbort (*C function*), 578
drivers_MCX_MCXA_MCXA366.I3C_MasterTransferAbortEDMA (*C function*), 594
drivers_MCX_MCXA_MCXA366.I3C_MasterTransferBlocking (*C function*), 576
drivers_MCX_MCXA_MCXA366.I3C_MasterTransferCreateHandle (*C function*), 577
drivers_MCX_MCXA_MCXA366.I3C_MasterTransferCreateHandleEDMA (*C function*), 592
drivers_MCX_MCXA_MCXA366.I3C_MasterTransferEDMA (*C function*), 593
drivers_MCX_MCXA_MCXA366.I3C_MasterTransferEDMAHandleIRQ (*C function*), 594
drivers_MCX_MCXA_MCXA366.I3C_MasterTransferGetCount (*C function*), 578
drivers_MCX_MCXA_MCXA366.I3C_MasterTransferGetCountEDMA (*C function*), 593
drivers_MCX_MCXA_MCXA366.I3C_MasterTransferHandleIRQ (*C function*), 578
drivers_MCX_MCXA_MCXA366.I3C_MasterTransferNonBlocking (*C function*), 577
drivers_MCX_MCXA_MCXA366.I3C_MasterWaitForCtrlDone (*C function*), 562
drivers_MCX_MCXA_MCXA366.I3C_MAX_DEVCNT (*C macro*), 557
drivers_MCX_MCXA_MCXA366.i3c_register_ibi_addr_t (*C type*), 587
drivers_MCX_MCXA_MCXA366.I3C_RETRY_TIMES (*C macro*), 557
drivers_MCX_MCXA_MCXA366.i3c_rx_term_ops_t (*C type*), 587
drivers_MCX_MCXA_MCXA366.i3c_rx_trigger_level_t (*C type*), 587
drivers_MCX_MCXA_MCXA366.i3c_slave_activity_state_t (*C type*), 607
drivers_MCX_MCXA_MCXA366.i3c_slave_config_t (*C type*), 607
drivers_MCX_MCXA_MCXA366.i3c_slave_edma_callback_t (*C type*), 611
drivers_MCX_MCXA_MCXA366.i3c_slave_edma_handle_t (*C type*), 611
drivers_MCX_MCXA_MCXA366.i3c_slave_edma_transfer_t (*C type*), 611
drivers_MCX_MCXA_MCXA366.i3c_slave_event_t (*C type*), 607
drivers_MCX_MCXA_MCXA366.i3c_slave_handle_t (*C type*), 607
drivers_MCX_MCXA_MCXA366.i3c_slave_isr_t (*C type*), 607
drivers_MCX_MCXA_MCXA366.i3c_slave_transfer_callback_t (*C type*), 607
drivers_MCX_MCXA_MCXA366.i3c_slave_transfer_event_t (*C type*), 607
drivers_MCX_MCXA_MCXA366.i3c_slave_transfer_t (*C type*), 607
drivers_MCX_MCXA_MCXA366.I3C_SlaveCheckAndClearError (*C function*), 566
drivers_MCX_MCXA_MCXA366.I3C_SlaveClearErrorStatusFlags (*C function*), 565, 598
drivers_MCX_MCXA_MCXA366.I3C_SlaveClearStatusFlags (*C function*), 565, 597
drivers_MCX_MCXA_MCXA366.I3C_SlaveDeinit (*C function*), 562, 596
drivers_MCX_MCXA_MCXA366.I3C_SlaveDisableInterrupts (*C function*), 567, 598
drivers_MCX_MCXA_MCXA366.I3C_SlaveEnable (*C function*), 563, 596
drivers_MCX_MCXA_MCXA366.I3C_SlaveEnableDMA (*C function*), 568, 599
drivers_MCX_MCXA_MCXA366.I3C_SlaveEnableInterrupts (*C function*), 566, 598
drivers_MCX_MCXA_MCXA366.I3C_SlaveGetActivityState (*C function*), 566, 598
drivers_MCX_MCXA_MCXA366.I3C_SlaveGetDefaultConfig (*C function*), 562, 596
drivers_MCX_MCXA_MCXA366.I3C_SlaveGetEnabledInterrupts (*C function*), 567, 599
drivers_MCX_MCXA_MCXA366.I3C_SlaveGetErrorStatusFlags (*C function*), 565, 597
drivers_MCX_MCXA_MCXA366.I3C_SlaveGetFifoCounts (*C function*), 570, 600
drivers_MCX_MCXA_MCXA366.I3C_SlaveGetPendingInterrupts (*C function*), 568, 599
drivers_MCX_MCXA_MCXA366.I3C_SlaveGetRxFifoAddress (*C function*), 569, 600
drivers_MCX_MCXA_MCXA366.I3C_SlaveGetStatusFlags (*C function*), 564, 596
drivers_MCX_MCXA_MCXA366.I3C_SlaveGetTxFifoAddress (*C function*), 569, 599
drivers_MCX_MCXA_MCXA366.I3C_SlaveInit (*C function*), 562, 596
drivers_MCX_MCXA_MCXA366.I3C_SlaveReceive (*C function*), 577, 600
drivers_MCX_MCXA_MCXA366.I3C_SlaveSend (*C function*), 577, 600
drivers_MCX_MCXA_MCXA366.I3C_SlaveSetWatermarks (*C function*), 569, 600
drivers_MCX_MCXA_MCXA366.I3C_SlaveTransferAbort (*C function*), 602

drivers_MCX_MCXA_MCXA366.I3C_SlaveTransferAbortEDMA (*C function*), 611
drivers_MCX_MCXA_MCXA366.I3C_SlaveTransferCreateHandle (*C function*), 601
drivers_MCX_MCXA_MCXA366.I3C_SlaveTransferCreateHandleEDMA (*C function*), 610
drivers_MCX_MCXA_MCXA366.I3C_SlaveTransferEDMA (*C function*), 610
drivers_MCX_MCXA_MCXA366.I3C_SlaveTransferEDMAHandleIRQ (*C function*), 611
drivers_MCX_MCXA_MCXA366.I3C_SlaveTransferGetCount (*C function*), 602
drivers_MCX_MCXA_MCXA366.I3C_SlaveTransferHandleIRQ (*C function*), 602
drivers_MCX_MCXA_MCXA366.I3C_SlaveTransferNonBlocking (*C function*), 601
drivers_MCX_MCXA_MCXA366.i3c_start_scl_delay_t (*C type*), 587
drivers_MCX_MCXA_MCXA366.i3c_timing_t (*C type*), 587
drivers_MCX_MCXA_MCXA366.i3c_tx_trigger_level_t (*C type*), 587
drivers_MCX_MCXA_MCXA366.ID_EXT (*C macro*), 334
drivers_MCX_MCXA_MCXA366.ID_STD_HIGH (*C macro*), 334
drivers_MCX_MCXA_MCXA366.ID_STD_LOW (*C macro*), 334
drivers_MCX_MCXA_MCXA366.input (*C var*), 764
drivers_MCX_MCXA_MCXA366.input_value (*C var*), 764
drivers_MCX_MCXA_MCXA366.INPUTMUX_AttachSignal (*C function*), 613
drivers_MCX_MCXA_MCXA366.INPUTMUX_Deinit (*C function*), 614
drivers_MCX_MCXA_MCXA366.INPUTMUX_Init (*C function*), 613
drivers_MCX_MCXA_MCXA366.interval (*C var*), 367, 468
drivers_MCX_MCXA_MCXA366.IRQ_ClearPendingIRQ (*C function*), 629
drivers_MCX_MCXA_MCXA366.IRQ_SetPriority (*C function*), 629
drivers_MCX_MCXA_MCXA366.kLpi2cMasterIrqs (*C var*), 671
drivers_MCX_MCXA_MCXA366.kLpi2cSlaveIrqs (*C var*), 671
drivers_MCX_MCXA_MCXA366.kVBAT_EnableClockToVddBat (*C macro*), 832
drivers_MCX_MCXA_MCXA366.kVBAT_EnableClockToVddMain (*C macro*), 832
drivers_MCX_MCXA_MCXA366.kVBAT_EnableClockToVddSys (*C macro*), 832
drivers_MCX_MCXA_MCXA366.kVBAT_EnableClockToVddWake (*C macro*), 832
drivers_MCX_MCXA_MCXA366.L1CACHE_DisableAllocation (*C function*), 205
drivers_MCX_MCXA_MCXA366.L1CACHE_DisableCodeCache (*C function*), 204
drivers_MCX_MCXA_MCXA366.L1CACHE_DisableParity (*C function*), 205
drivers_MCX_MCXA_MCXA366.L1CACHE_EnableAllocation (*C function*), 205
drivers_MCX_MCXA_MCXA366.L1CACHE_EnableCodeCache (*C function*), 204
drivers_MCX_MCXA_MCXA366.L1CACHE_EnableParity (*C function*), 205
drivers_MCX_MCXA_MCXA366.L1CACHE_InvalidateCodeCache (*C function*), 205
drivers_MCX_MCXA_MCXA366.lowpowerFilterEnable (*C var*), 781
drivers_MCX_MCXA_MCXA366.LPADC_CALIBRATION_READY_TIMEOUT (*C macro*), 640
drivers_MCX_MCXA_MCXA366.lpadc_calibration_value_t (*C type*), 640
drivers_MCX_MCXA_MCXA366.LPADC_ClearStatusFlags (*C function*), 642
drivers_MCX_MCXA_MCXA366.LPADC_ClearTriggerStatusFlags (*C function*), 642
drivers_MCX_MCXA_MCXA366.lpadc_config_t (*C struct*), 649
drivers_MCX_MCXA_MCXA366.lpadc_config_t.conversionAverageMode (*C var*), 649
drivers_MCX_MCXA_MCXA366.lpadc_config_t.convPauseDelay (*C var*), 650
drivers_MCX_MCXA_MCXA366.lpadc_config_t.enableAnalogPreliminary (*C var*), 650
drivers_MCX_MCXA_MCXA366.lpadc_config_t.enableConvPause (*C var*), 650
drivers_MCX_MCXA_MCXA366.lpadc_config_t.enableInDozeMode (*C var*), 649
drivers_MCX_MCXA_MCXA366.lpadc_config_t.enableInternalClock (*C var*), 649
drivers_MCX_MCXA_MCXA366.lpadc_config_t.enableVref1LowVoltage (*C var*), 649
drivers_MCX_MCXA_MCXA366.lpadc_config_t.FIFOWatermark (*C var*), 650
drivers_MCX_MCXA_MCXA366.lpadc_config_t.powerLevelMode (*C var*), 650
drivers_MCX_MCXA_MCXA366.lpadc_config_t.powerUpDelay (*C var*), 650
drivers_MCX_MCXA_MCXA366.lpadc_config_t.referenceVoltageSource (*C var*), 650
drivers_MCX_MCXA_MCXA366.lpadc_config_t.triggerPriorityPolicy (*C var*), 650
drivers_MCX_MCXA_MCXA366.lpadc_conv_command_config_t (*C struct*), 650
drivers_MCX_MCXA_MCXA366.lpadc_conv_command_config_t.chainedNextCommandNumber (*C var*), 651
drivers_MCX_MCXA_MCXA366.lpadc_conv_command_config_t.channelBNumber (*C var*), 651
drivers_MCX_MCXA_MCXA366.lpadc_conv_command_config_t.channelBScaleMode (*C var*), 650

drivers_MCX_MCXA_MCXA366.lpadc_conv_command_config_t.channelNumber (C var), 651
drivers_MCX_MCXA_MCXA366.lpadc_conv_command_config_t.conversionResolutionMode (C var), 651
drivers_MCX_MCXA_MCXA366.lpadc_conv_command_config_t.enableAutoChannelIncrement (C var), 651
drivers_MCX_MCXA_MCXA366.lpadc_conv_command_config_t.enableWaitTrigger (C var), 651
drivers_MCX_MCXA_MCXA366.lpadc_conv_command_config_t.hardwareAverageMode (C var), 651
drivers_MCX_MCXA_MCXA366.lpadc_conv_command_config_t.hardwareCompareMode (C var), 651
drivers_MCX_MCXA_MCXA366.lpadc_conv_command_config_t.hardwareCompareValueHigh (C var), 651
drivers_MCX_MCXA_MCXA366.lpadc_conv_command_config_t.hardwareCompareValueLow (C var), 651
drivers_MCX_MCXA_MCXA366.lpadc_conv_command_config_t.loopCount (C var), 651
drivers_MCX_MCXA_MCXA366.lpadc_conv_command_config_t.sampleChannelMode (C var), 650
drivers_MCX_MCXA_MCXA366.lpadc_conv_command_config_t.sampleScaleMode (C var), 650
drivers_MCX_MCXA_MCXA366.lpadc_conv_command_config_t.sampleTimeMode (C var), 651
drivers_MCX_MCXA_MCXA366.lpadc_conv_result_t (C struct), 652
drivers_MCX_MCXA_MCXA366.lpadc_conv_result_t.commandIdSource (C var), 652
drivers_MCX_MCXA_MCXA366.lpadc_conv_result_t.convValue (C var), 652
drivers_MCX_MCXA_MCXA366.lpadc_conv_result_t.loopCountIndex (C var), 652
drivers_MCX_MCXA_MCXA366.lpadc_conv_result_t.triggerIdSource (C var), 652
drivers_MCX_MCXA_MCXA366.lpadc_conv_trigger_config_t (C struct), 651
drivers_MCX_MCXA_MCXA366.lpadc_conv_trigger_config_t.delayPower (C var), 652
drivers_MCX_MCXA_MCXA366.lpadc_conv_trigger_config_t.enableHardwareTrigger (C var), 652
drivers_MCX_MCXA_MCXA366.lpadc_conv_trigger_config_t.priority (C var), 652
drivers_MCX_MCXA_MCXA366.lpadc_conv_trigger_config_t.targetCommandId (C var), 652
drivers_MCX_MCXA_MCXA366.lpadc_conversion_average_mode_t (C type), 639
drivers_MCX_MCXA_MCXA366.LPADC_CONVERSION_COMPLETE_TIMEOUT (C macro), 640
drivers_MCX_MCXA_MCXA366.lpadc_conversion_resolution_mode_t (C type), 639
drivers_MCX_MCXA_MCXA366.LPADC_Deinit (C function), 641
drivers_MCX_MCXA_MCXA366.LPADC_DisableInterrupts (C function), 642
drivers_MCX_MCXA_MCXA366.LPADC_DoAutoCalibration (C function), 645
drivers_MCX_MCXA_MCXA366.LPADC_DoOffsetCalibration (C function), 646
drivers_MCX_MCXA_MCXA366.LPADC_DoResetConfig (C function), 641
drivers_MCX_MCXA_MCXA366.LPADC_DoResetFIFO (C function), 641
drivers_MCX_MCXA_MCXA366.LPADC_DoSoftwareTrigger (C function), 644
drivers_MCX_MCXA_MCXA366.LPADC_Enable (C function), 641
drivers_MCX_MCXA_MCXA366.LPADC_EnableCalibration (C function), 645
drivers_MCX_MCXA_MCXA366.LPADC_EnableExtraCycle (C function), 648
drivers_MCX_MCXA_MCXA366.LPADC_EnableFIFOWatermarkDMA (C function), 643
drivers_MCX_MCXA_MCXA366.LPADC_EnableHardwareTriggerCommandSelection (C function), 644
drivers_MCX_MCXA_MCXA366.LPADC_EnableHighSpeedConversionMode (C function), 648
drivers_MCX_MCXA_MCXA366.LPADC_EnableInterrupts (C function), 642
drivers_MCX_MCXA_MCXA366.LPADC_EnableJustifiedLeft (C function), 649
drivers_MCX_MCXA_MCXA366.LPADC_EnableOffsetCalibration (C function), 646
drivers_MCX_MCXA_MCXA366.LPADC_FinishAutoCalibration (C function), 647
drivers_MCX_MCXA_MCXA366.LPADC_GAIN_CAL_READY_TIMEOUT (C macro), 640
drivers_MCX_MCXA_MCXA366.LPADC_GET_ACTIVE_COMMAND_STATUS (C macro), 640
drivers_MCX_MCXA_MCXA366.LPADC_GET_ACTIVE_TRIGGER_STATUE (C macro), 640
drivers_MCX_MCXA_MCXA366.LPADC_GetCalibrationValue (C function), 647
drivers_MCX_MCXA_MCXA366.LPADC_GetConvResult (C function), 643
drivers_MCX_MCXA_MCXA366.LPADC_GetConvResultBlocking (C function), 643
drivers_MCX_MCXA_MCXA366.LPADC_GetConvResultCount (C function), 643
drivers_MCX_MCXA_MCXA366.LPADC_GetDefaultConfig (C function), 641

drivers_MCX_MCXA_MCXA366.LPADC_GetDefaultConvCommandConfig (*C function*), 644
drivers_MCX_MCXA_MCXA366.LPADC_GetDefaultConvTriggerConfig (*C function*), 643
drivers_MCX_MCXA_MCXA366.LPADC_GetHighSpeedTrimValue (*C function*), 648
drivers_MCX_MCXA_MCXA366.LPADC_GetOffsetValue (*C function*), 646
drivers_MCX_MCXA_MCXA366.LPADC_GetStatusFlags (*C function*), 641
drivers_MCX_MCXA_MCXA366.LPADC_GetTriggerStatusFlags (*C function*), 642
drivers_MCX_MCXA_MCXA366.LPADC_GetTuneValue (*C function*), 649
drivers_MCX_MCXA_MCXA366.lpadc_hardware_average_mode_t (*C type*), 638
drivers_MCX_MCXA_MCXA366.lpadc_hardware_compare_mode_t (*C type*), 639
drivers_MCX_MCXA_MCXA366.LPADC_Init (*C function*), 641
drivers_MCX_MCXA_MCXA366.lpadc_offset_calibration_mode_t (*C type*), 639
drivers_MCX_MCXA_MCXA366.lpadc_power_level_mode_t (*C type*), 639
drivers_MCX_MCXA_MCXA366.LPADC_PrepareAutoCalibration (*C function*), 647
drivers_MCX_MCXA_MCXA366.lpadc_reference_voltage_source_t (*C type*), 639
drivers_MCX_MCXA_MCXA366.LPADC_RequestHighSpeedModeTrim (*C function*), 648
drivers_MCX_MCXA_MCXA366.lpadc_sample_channel_mode_t (*C type*), 638
drivers_MCX_MCXA_MCXA366.lpadc_sample_scale_mode_t (*C type*), 638
drivers_MCX_MCXA_MCXA366.lpadc_sample_time_mode_t (*C type*), 639
drivers_MCX_MCXA_MCXA366.LPADC_SetCalibrationValue (*C function*), 647
drivers_MCX_MCXA_MCXA366.LPADC_SetConvCommandConfig (*C function*), 644
drivers_MCX_MCXA_MCXA366.LPADC_SetConvTriggerConfig (*C function*), 643
drivers_MCX_MCXA_MCXA366.LPADC_SetHighSpeedTrimValue (*C function*), 648
drivers_MCX_MCXA_MCXA366.LPADC_SetOffsetCalibrationMode (*C function*), 646
drivers_MCX_MCXA_MCXA366.LPADC_SetOffsetValue (*C function*), 645, 646
drivers_MCX_MCXA_MCXA366.LPADC_SetTuneValue (*C function*), 648
drivers_MCX_MCXA_MCXA366.lpadc_trigger_priority_policy_t (*C type*), 639
drivers_MCX_MCXA_MCXA366.lpadc_tune_value_t (*C type*), 640
drivers_MCX_MCXA_MCXA366.LPADC_USE_FIXED_POINT_GAIN_CALCULATION (*C macro*), 640
drivers_MCX_MCXA_MCXA366.LPCMP_CCR1_COUTA_CFG (*C macro*), 667
drivers_MCX_MCXA_MCXA366.LPCMP_CCR1_COUTA_CFG_MASK (*C macro*), 667
drivers_MCX_MCXA_MCXA366.LPCMP_CCR1_COUTA_CFG_SHIFT (*C macro*), 667
drivers_MCX_MCXA_MCXA366.LPCMP_CCR1_EVT_SEL_CFG (*C macro*), 667
drivers_MCX_MCXA_MCXA366.LPCMP_CCR1_EVT_SEL_CFG_MASK (*C macro*), 667
drivers_MCX_MCXA_MCXA366.LPCMP_CCR1_EVT_SEL_CFG_SHIFT (*C macro*), 667
drivers_MCX_MCXA_MCXA366.LPCMP_ClearInputChangedFlags (*C function*), 662
drivers_MCX_MCXA_MCXA366.LPCMP_ClearStatusFlags (*C function*), 660
drivers_MCX_MCXA_MCXA366.lpcmp_close_window_event_t (*C type*), 666
drivers_MCX_MCXA_MCXA366.lpcmp_config_t (*C type*), 667
drivers_MCX_MCXA_MCXA366.lpcmp_couta_signal_t (*C type*), 666
drivers_MCX_MCXA_MCXA366.lpcmp_dac_config_t (*C type*), 667
drivers_MCX_MCXA_MCXA366.lpcmp_dac_reference_voltage_source_t (*C type*), 666
drivers_MCX_MCXA_MCXA366.LPCMP_Deinit (*C function*), 659
drivers_MCX_MCXA_MCXA366.LPCMP_DisableInterrupts (*C function*), 660
drivers_MCX_MCXA_MCXA366.LPCMP_Enable (*C function*), 659
drivers_MCX_MCXA_MCXA366.LPCMP_EnableDMA (*C function*), 659
drivers_MCX_MCXA_MCXA366.LPCMP_EnableInterrupts (*C function*), 660
drivers_MCX_MCXA_MCXA366.LPCMP_EnableRoundRobinInternalTimer (*C function*), 661
drivers_MCX_MCXA_MCXA366.LPCMP_EnableRoundRobinMode (*C function*), 661
drivers_MCX_MCXA_MCXA366.LPCMP_EnableWindowMode (*C function*), 660
drivers_MCX_MCXA_MCXA366.lpcmp_filter_config_t (*C type*), 666
drivers_MCX_MCXA_MCXA366.lpcmp_functional_source_clock_t (*C type*), 666
drivers_MCX_MCXA_MCXA366.LPCMP_GetComparisonResult (*C function*), 662
drivers_MCX_MCXA_MCXA366.LPCMP_GetDefaultConfig (*C function*), 659
drivers_MCX_MCXA_MCXA366.LPCMP_GetInputChangedFlags (*C function*), 662
drivers_MCX_MCXA_MCXA366.LPCMP_GetStatusFlags (*C function*), 660
drivers_MCX_MCXA_MCXA366.lpcmp_hysteresis_mode_t (*C type*), 666
drivers_MCX_MCXA_MCXA366.LPCMP_Init (*C function*), 658

drivers_MCX_MCXA_MCXA366.lpcmp_minus_input_src_t (*C type*), 667
drivers_MCX_MCXA_MCXA366.lpcmp_plus_input_src_t (*C type*), 667
drivers_MCX_MCXA_MCXA366.lpcmp_power_mode_t (*C type*), 666
drivers_MCX_MCXA_MCXA366.lpcmp_roundrobin_clock_source_t (*C type*), 666
drivers_MCX_MCXA_MCXA366.lpcmp_roundrobin_config_t (*C type*), 667
drivers_MCX_MCXA_MCXA366.lpcmp_roundrobin_fixedmuxport_t (*C type*), 666
drivers_MCX_MCXA_MCXA366.lpcmp_roundrobin_trigger_source_t (*C type*), 666
drivers_MCX_MCXA_MCXA366.LPCMP_SetDACConfig (*C function*), 660
drivers_MCX_MCXA_MCXA366.LPCMP_SetFilterConfig (*C function*), 660
drivers_MCX_MCXA_MCXA366.LPCMP_SetInputChannels (*C function*), 659
drivers_MCX_MCXA_MCXA366.LPCMP_SetPreSetValue (*C function*), 661
drivers_MCX_MCXA_MCXA366.LPCMP_SetRoundRobinConfig (*C function*), 661
drivers_MCX_MCXA_MCXA366.LPCMP_SetRoundRobinInternalTimer (*C function*), 661
drivers_MCX_MCXA_MCXA366.LPCMP_SetWindowControl (*C function*), 661
drivers_MCX_MCXA_MCXA366.lpcmp_window_control_config_t (*C type*), 667
drivers_MCX_MCXA_MCXA366.LPI2C_CheckForBusyBus (*C function*), 672
drivers_MCX_MCXA_MCXA366.lpi2c_data_match_config_mode_t (*C type*), 683
drivers_MCX_MCXA_MCXA366.lpi2c_data_match_config_t (*C type*), 683
drivers_MCX_MCXA_MCXA366.lpi2c_direction_t (*C type*), 683
drivers_MCX_MCXA_MCXA366.LPI2C_DriverIRQHandler (*C function*), 670
drivers_MCX_MCXA_MCXA366.LPI2C_GetInstance (*C function*), 671
drivers_MCX_MCXA_MCXA366.lpi2c_host_request_polarity_t (*C type*), 683
drivers_MCX_MCXA_MCXA366.lpi2c_host_request_source_t (*C type*), 683
drivers_MCX_MCXA_MCXA366.lpi2c_master_config_t (*C type*), 683
drivers_MCX_MCXA_MCXA366.lpi2c_master_edma_handle_t (*C type*), 688
drivers_MCX_MCXA_MCXA366.lpi2c_master_edma_transfer_callback_t (*C type*), 688
drivers_MCX_MCXA_MCXA366.lpi2c_master_handle_t (*C type*), 683
drivers_MCX_MCXA_MCXA366.lpi2c_master_isr_t (*C type*), 684
drivers_MCX_MCXA_MCXA366.lpi2c_master_pin_config_t (*C type*), 683
drivers_MCX_MCXA_MCXA366.lpi2c_master_transfer_callback_t (*C type*), 683
drivers_MCX_MCXA_MCXA366.lpi2c_master_transfer_t (*C type*), 683
drivers_MCX_MCXA_MCXA366.LPI2C_MasterCheckAndClearError (*C function*), 672
drivers_MCX_MCXA_MCXA366.LPI2C_MasterClearStatusFlags (*C function*), 673
drivers_MCX_MCXA_MCXA366.LPI2C_MasterConfigureDataMatch (*C function*), 672
drivers_MCX_MCXA_MCXA366.LPI2C_MasterCreateEDMAHandle (*C function*), 687
drivers_MCX_MCXA_MCXA366.LPI2C_MasterDeinit (*C function*), 672
drivers_MCX_MCXA_MCXA366.LPI2C_MasterDisableInterrupts (*C function*), 674
drivers_MCX_MCXA_MCXA366.LPI2C_MasterEnable (*C function*), 673
drivers_MCX_MCXA_MCXA366.LPI2C_MasterEnableDMA (*C function*), 674
drivers_MCX_MCXA_MCXA366.LPI2C_MasterEnableInterrupts (*C function*), 674
drivers_MCX_MCXA_MCXA366.LPI2C_MasterGetBusIdleState (*C function*), 676
drivers_MCX_MCXA_MCXA366.LPI2C_MasterGetDefaultConfig (*C function*), 671
drivers_MCX_MCXA_MCXA366.LPI2C_MasterGetEnabledInterrupts (*C function*), 674
drivers_MCX_MCXA_MCXA366.LPI2C_MasterGetFifoCounts (*C function*), 675
drivers_MCX_MCXA_MCXA366.LPI2C_MasterGetRxFifoAddress (*C function*), 675
drivers_MCX_MCXA_MCXA366.LPI2C_MasterGetStatusFlags (*C function*), 673
drivers_MCX_MCXA_MCXA366.LPI2C_MasterGetTxFifoAddress (*C function*), 674
drivers_MCX_MCXA_MCXA366.LPI2C_MasterInit (*C function*), 672
drivers_MCX_MCXA_MCXA366.LPI2C_MasterReceive (*C function*), 677
drivers_MCX_MCXA_MCXA366.LPI2C_MasterRepeatedStart (*C function*), 676
drivers_MCX_MCXA_MCXA366.LPI2C_MasterReset (*C function*), 673
drivers_MCX_MCXA_MCXA366.LPI2C_MasterSend (*C function*), 677
drivers_MCX_MCXA_MCXA366.LPI2C_MasterSetBaudRate (*C function*), 675
drivers_MCX_MCXA_MCXA366.LPI2C_MasterSetWatermarks (*C function*), 675
drivers_MCX_MCXA_MCXA366.LPI2C_MasterStart (*C function*), 676
drivers_MCX_MCXA_MCXA366.LPI2C_MasterStop (*C function*), 677
drivers_MCX_MCXA_MCXA366.LPI2C_MasterTransferAbort (*C function*), 679
drivers_MCX_MCXA_MCXA366.LPI2C_MasterTransferAbortEDMA (*C function*), 688

drivers_MCX_MCXA_MCXA366.LPI2C_MasterTransferBlocking (*C function*), 678
drivers_MCX_MCXA_MCXA366.LPI2C_MasterTransferCreateHandle (*C function*), 678
drivers_MCX_MCXA_MCXA366.LPI2C_MasterTransferEDMA (*C function*), 687
drivers_MCX_MCXA_MCXA366.LPI2C_MasterTransferGetCount (*C function*), 679
drivers_MCX_MCXA_MCXA366.LPI2C_MasterTransferGetCountEDMA (*C function*), 688
drivers_MCX_MCXA_MCXA366.LPI2C_MasterTransferHandleIRQ (*C function*), 679
drivers_MCX_MCXA_MCXA366.LPI2C_MasterTransferNonBlocking (*C function*), 678
drivers_MCX_MCXA_MCXA366.lpi2c_slave_address_match_t (*C type*), 697
drivers_MCX_MCXA_MCXA366.lpi2c_slave_config_t (*C type*), 697
drivers_MCX_MCXA_MCXA366.lpi2c_slave_handle_t (*C type*), 698
drivers_MCX_MCXA_MCXA366.lpi2c_slave_transfer_callback_t (*C type*), 698
drivers_MCX_MCXA_MCXA366.lpi2c_slave_transfer_event_t (*C type*), 697
drivers_MCX_MCXA_MCXA366.lpi2c_slave_transfer_t (*C type*), 698
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveClearStatusFlags (*C function*), 691
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveDeinit (*C function*), 690
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveDisableInterrupts (*C function*), 692
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveEnable (*C function*), 690
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveEnableAckStall (*C function*), 693
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveEnableDMA (*C function*), 692
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveEnableInterrupts (*C function*), 691
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveGetBusIdleState (*C function*), 692
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveGetDefaultConfig (*C function*), 689
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveGetEnabledInterrupts (*C function*), 692
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveGetReceivedAddress (*C function*), 693
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveGetStatusFlags (*C function*), 691
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveInit (*C function*), 690
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveReceive (*C function*), 693
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveReset (*C function*), 690
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveSend (*C function*), 693
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveTransferAbort (*C function*), 695
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveTransferCreateHandle (*C function*), 693
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveTransferGetCount (*C function*), 694
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveTransferHandleIRQ (*C function*), 695
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveTransferNonBlocking (*C function*), 694
drivers_MCX_MCXA_MCXA366.LPI2C_SlaveTransmitAck (*C function*), 692
drivers_MCX_MCXA_MCXA366.LPSPI_CheckTransferArgument (*C function*), 704
drivers_MCX_MCXA_MCXA366.LPSPI_ClearStatusFlags (*C function*), 703
drivers_MCX_MCXA_MCXA366.lpspi_clock_phase_t (*C type*), 719
drivers_MCX_MCXA_MCXA366.lpspi_clock_polarity_t (*C type*), 719
drivers_MCX_MCXA_MCXA366.lpspi_data_out_config_t (*C type*), 719
drivers_MCX_MCXA_MCXA366.LPSPI_Deinit (*C function*), 702
drivers_MCX_MCXA_MCXA366.lpspi_delay_type_t (*C type*), 719
drivers_MCX_MCXA_MCXA366.LPSPI_DisableDMA (*C function*), 704
drivers_MCX_MCXA_MCXA366.LPSPI_DisableInterrupts (*C function*), 703
drivers_MCX_MCXA_MCXA366.LPSPI_DriverIRQHandler (*C function*), 711
drivers_MCX_MCXA_MCXA366.LPSPI_DUMMY_DATA (*C macro*), 720
drivers_MCX_MCXA_MCXA366.LPSPI_Enable (*C function*), 702
drivers_MCX_MCXA_MCXA366.LPSPI_EnableDMA (*C function*), 704
drivers_MCX_MCXA_MCXA366.LPSPI_EnableInterrupts (*C function*), 703
drivers_MCX_MCXA_MCXA366.LPSPI_FlushFifo (*C function*), 705
drivers_MCX_MCXA_MCXA366.LPSPI_GetInstance (*C function*), 702
drivers_MCX_MCXA_MCXA366.LPSPI_GetRxFifoCount (*C function*), 703
drivers_MCX_MCXA_MCXA366.LPSPI_GetRxFifoSize (*C function*), 702
drivers_MCX_MCXA_MCXA366.LPSPI_GetRxRegisterAddress (*C function*), 704
drivers_MCX_MCXA_MCXA366.LPSPI_GetStatusFlags (*C function*), 702
drivers_MCX_MCXA_MCXA366.LPSPI_GetTcr (*C function*), 703
drivers_MCX_MCXA_MCXA366.LPSPI_GetTxFifoCount (*C function*), 703
drivers_MCX_MCXA_MCXA366.LPSPI_GetTxFifoSize (*C function*), 702

drivers_MCX_MCXA_MCXA366.LPSPI_GetTxRegisterAddress (*C function*), 704
drivers_MCX_MCXA_MCXA366.lpspi_host_request_select_t (*C type*), 719
drivers_MCX_MCXA_MCXA366.LPSPI_IsMaster (*C function*), 705
drivers_MCX_MCXA_MCXA366.lpspi_master_config_t (*C type*), 719
drivers_MCX_MCXA_MCXA366.lpspi_master_edma_handle_t (*C type*), 725
drivers_MCX_MCXA_MCXA366.lpspi_master_edma_transfer_callback_t (*C type*), 725
drivers_MCX_MCXA_MCXA366.lpspi_master_handle_t (*C type*), 719
drivers_MCX_MCXA_MCXA366.LPSPI_MASTER_PCS_MASK (*C macro*), 720
drivers_MCX_MCXA_MCXA366.LPSPI_MASTER_PCS_SHIFT (*C macro*), 720
drivers_MCX_MCXA_MCXA366.lpspi_master_slave_mode_t (*C type*), 718
drivers_MCX_MCXA_MCXA366.lpspi_master_transfer_callback_t (*C type*), 719
drivers_MCX_MCXA_MCXA366.LPSPI_MasterGetDefaultConfig (*C function*), 701
drivers_MCX_MCXA_MCXA366.LPSPI_MasterInit (*C function*), 701
drivers_MCX_MCXA_MCXA366.LPSPI_MasterSetBaudRate (*C function*), 706
drivers_MCX_MCXA_MCXA366.LPSPI_MasterSetDelayScaler (*C function*), 707
drivers_MCX_MCXA_MCXA366.LPSPI_MasterSetDelayTimes (*C function*), 707
drivers_MCX_MCXA_MCXA366.LPSPI_MasterTransferAbort (*C function*), 709
drivers_MCX_MCXA_MCXA366.LPSPI_MasterTransferAbortEDMA (*C function*), 727
drivers_MCX_MCXA_MCXA366.LPSPI_MasterTransferBlocking (*C function*), 708
drivers_MCX_MCXA_MCXA366.LPSPI_MasterTransferCreateHandle (*C function*), 708
drivers_MCX_MCXA_MCXA366.LPSPI_MasterTransferCreateHandleEDMA (*C function*), 726
drivers_MCX_MCXA_MCXA366.LPSPI_MasterTransferEDMA (*C function*), 726
drivers_MCX_MCXA_MCXA366.LPSPI_MasterTransferEDMALite (*C function*), 727
drivers_MCX_MCXA_MCXA366.LPSPI_MasterTransferGetCount (*C function*), 709
drivers_MCX_MCXA_MCXA366.LPSPI_MasterTransferGetCountEDMA (*C function*), 728
drivers_MCX_MCXA_MCXA366.LPSPI_MasterTransferHandleIRQ (*C function*), 710
drivers_MCX_MCXA_MCXA366.LPSPI_MasterTransferNonBlocking (*C function*), 709
drivers_MCX_MCXA_MCXA366.LPSPI_MasterTransferPrepareEDMALite (*C function*), 727
drivers_MCX_MCXA_MCXA366.lpspi_match_config_t (*C type*), 719
drivers_MCX_MCXA_MCXA366.lpspi_pcs_polarity_config_t (*C type*), 718
drivers_MCX_MCXA_MCXA366.lpspi_pin_config_t (*C type*), 719
drivers_MCX_MCXA_MCXA366.LPSPI_ReadData (*C function*), 708
drivers_MCX_MCXA_MCXA366.LPSPI_Reset (*C function*), 702
drivers_MCX_MCXA_MCXA366.LPSPI_SelectTransferPCS (*C function*), 705
drivers_MCX_MCXA_MCXA366.LPSPI_SetAllPcsPolarity (*C function*), 706
drivers_MCX_MCXA_MCXA366.LPSPI_SetDummyData (*C function*), 708
drivers_MCX_MCXA_MCXA366.LPSPI_SetFifoWatermarks (*C function*), 705
drivers_MCX_MCXA_MCXA366.LPSPI_SetFrameSize (*C function*), 706
drivers_MCX_MCXA_MCXA366.LPSPI_SetMasterSlaveMode (*C function*), 705
drivers_MCX_MCXA_MCXA366.LPSPI_SetPCSContinous (*C function*), 705
drivers_MCX_MCXA_MCXA366.lpspi_shift_direction_t (*C type*), 719
drivers_MCX_MCXA_MCXA366.lpspi_slave_config_t (*C type*), 719
drivers_MCX_MCXA_MCXA366.lpspi_slave_edma_handle_t (*C type*), 725
drivers_MCX_MCXA_MCXA366.lpspi_slave_edma_transfer_callback_t (*C type*), 725
drivers_MCX_MCXA_MCXA366.lpspi_slave_handle_t (*C type*), 719
drivers_MCX_MCXA_MCXA366.LPSPI_SLAVE_PCS_MASK (*C macro*), 720
drivers_MCX_MCXA_MCXA366.LPSPI_SLAVE_PCS_SHIFT (*C macro*), 720
drivers_MCX_MCXA_MCXA366.lpspi_slave_transfer_callback_t (*C type*), 720
drivers_MCX_MCXA_MCXA366.LPSPI_SlaveGetDefaultConfig (*C function*), 701
drivers_MCX_MCXA_MCXA366.LPSPI_SlaveInit (*C function*), 701
drivers_MCX_MCXA_MCXA366.LPSPI_SlaveTransferAbort (*C function*), 711
drivers_MCX_MCXA_MCXA366.LPSPI_SlaveTransferAbortEDMA (*C function*), 729
drivers_MCX_MCXA_MCXA366.LPSPI_SlaveTransferCreateHandle (*C function*), 710
drivers_MCX_MCXA_MCXA366.LPSPI_SlaveTransferCreateHandleEDMA (*C function*), 728
drivers_MCX_MCXA_MCXA366.LPSPI_SlaveTransferEDMA (*C function*), 728
drivers_MCX_MCXA_MCXA366.LPSPI_SlaveTransferGetCount (*C function*), 710
drivers_MCX_MCXA_MCXA366.LPSPI_SlaveTransferGetCountEDMA (*C function*), 729
drivers_MCX_MCXA_MCXA366.LPSPI_SlaveTransferHandleIRQ (*C function*), 711

drivers_MCX_MCXA_MCXA366.LPSPI_SlaveTransferNonBlocking (*C function*), 710
drivers_MCX_MCXA_MCXA366.lpspi_transfer_t (*C type*), 720
drivers_MCX_MCXA_MCXA366.lpspi_transfer_width_t (*C type*), 719
drivers_MCX_MCXA_MCXA366.LPSPI_WaitTxFifoEmpty (*C function*), 711
drivers_MCX_MCXA_MCXA366.lpspi_which_pcs_t (*C type*), 718
drivers_MCX_MCXA_MCXA366.LPSPI_WriteData (*C function*), 708
drivers_MCX_MCXA_MCXA366.LPTMR_ClearStatusFlags (*C function*), 734
drivers_MCX_MCXA_MCXA366.lptmr_config_t (*C type*), 738
drivers_MCX_MCXA_MCXA366.LPTMR_Deinit (*C function*), 733
drivers_MCX_MCXA_MCXA366.LPTMR_DisableInterrupts (*C function*), 734
drivers_MCX_MCXA_MCXA366.LPTMR_EnableInterrupts (*C function*), 734
drivers_MCX_MCXA_MCXA366.LPTMR_EnableTimerDMA (*C function*), 738
drivers_MCX_MCXA_MCXA366.LPTMR_GetCurrentTimerCount (*C function*), 735
drivers_MCX_MCXA_MCXA366.LPTMR_GetDefaultConfig (*C function*), 733
drivers_MCX_MCXA_MCXA366.LPTMR_GetEnabledInterrupts (*C function*), 734
drivers_MCX_MCXA_MCXA366.LPTMR_GetStatusFlags (*C function*), 734
drivers_MCX_MCXA_MCXA366.LPTMR_Init (*C function*), 733
drivers_MCX_MCXA_MCXA366.lptmr_interrupt_enable_t (*C type*), 738
drivers_MCX_MCXA_MCXA366.lptmr_pin_polarity_t (*C type*), 737
drivers_MCX_MCXA_MCXA366.lptmr_pin_select_t (*C type*), 737
drivers_MCX_MCXA_MCXA366.lptmr_prescaler_clock_select_t (*C type*), 738
drivers_MCX_MCXA_MCXA366.lptmr_prescaler_glitch_value_t (*C type*), 738
drivers_MCX_MCXA_MCXA366.LPTMR_SetTimerPeriod (*C function*), 734
drivers_MCX_MCXA_MCXA366.LPTMR_StartTimer (*C function*), 735
drivers_MCX_MCXA_MCXA366.lptmr_status_flags_t (*C type*), 738
drivers_MCX_MCXA_MCXA366.LPTMR_StopTimer (*C function*), 735
drivers_MCX_MCXA_MCXA366.lptmr_timer_mode_t (*C type*), 738
drivers_MCX_MCXA_MCXA366.LPUART_ClearStatusFlags (*C function*), 742
drivers_MCX_MCXA_MCXA366.lpuart_config_t (*C type*), 756
drivers_MCX_MCXA_MCXA366.lpuart_data_bits_t (*C type*), 756
drivers_MCX_MCXA_MCXA366.LPUART_Deinit (*C function*), 740
drivers_MCX_MCXA_MCXA366.LPUART_DisableInterrupts (*C function*), 743
drivers_MCX_MCXA_MCXA366.LPUART_DriverIRQHandler (*C function*), 750
drivers_MCX_MCXA_MCXA366.lpuart_edma_handle_t (*C type*), 763
drivers_MCX_MCXA_MCXA366.lpuart_edma_transfer_callback_t (*C type*), 763
drivers_MCX_MCXA_MCXA366.LPUART_Enable9bitMode (*C function*), 741
drivers_MCX_MCXA_MCXA366.LPUART_EnableInterrupts (*C function*), 743
drivers_MCX_MCXA_MCXA366.LPUART_EnableMatchAddress (*C function*), 741
drivers_MCX_MCXA_MCXA366.LPUART_EnableRx (*C function*), 744
drivers_MCX_MCXA_MCXA366.LPUART_EnableRxDMA (*C function*), 744
drivers_MCX_MCXA_MCXA366.LPUART_EnableTx (*C function*), 744
drivers_MCX_MCXA_MCXA366.LPUART_EnableTxDMA (*C function*), 744
drivers_MCX_MCXA_MCXA366.LPUART_GetDataRegisterAddress (*C function*), 743
drivers_MCX_MCXA_MCXA366.LPUART_GetDefaultConfig (*C function*), 740
drivers_MCX_MCXA_MCXA366.LPUART_GetEnabledInterrupts (*C function*), 743
drivers_MCX_MCXA_MCXA366.LPUART_GetInstance (*C function*), 744
drivers_MCX_MCXA_MCXA366.LPUART_GetRxFifoCount (*C function*), 745
drivers_MCX_MCXA_MCXA366.LPUART_GetStatusFlags (*C function*), 742
drivers_MCX_MCXA_MCXA366.LPUART_GetTxFifoCount (*C function*), 745
drivers_MCX_MCXA_MCXA366.lpuart_handle_t (*C type*), 756
drivers_MCX_MCXA_MCXA366.lpuart_idle_config_t (*C type*), 756
drivers_MCX_MCXA_MCXA366.lpuart_idle_type_select_t (*C type*), 756
drivers_MCX_MCXA_MCXA366.LPUART_Init (*C function*), 739
drivers_MCX_MCXA_MCXA366.lpuart_isr_t (*C type*), 756
drivers_MCX_MCXA_MCXA366.lpuart_parity_mode_t (*C type*), 756
drivers_MCX_MCXA_MCXA366.LPUART_ReadBlocking (*C function*), 746
drivers_MCX_MCXA_MCXA366.LPUART_ReadBlocking16bit (*C function*), 746
drivers_MCX_MCXA_MCXA366.LPUART_ReadByte (*C function*), 745

drivers_MCX_MCXA_MCXA366.LPUART_ReceiveEDMA (*C function*), 761
drivers_MCX_MCXA_MCXA366.LPUART_SendAddress (*C function*), 745
drivers_MCX_MCXA_MCXA366.LPUART_SendEDMA (*C function*), 761
drivers_MCX_MCXA_MCXA366.LPUART_SetBaudRate (*C function*), 740
drivers_MCX_MCXA_MCXA366.LPUART_SetMatchAddress (*C function*), 741
drivers_MCX_MCXA_MCXA366.LPUART_SetRxFifoWatermark (*C function*), 741
drivers_MCX_MCXA_MCXA366.LPUART_SetTxFifoWatermark (*C function*), 742
drivers_MCX_MCXA_MCXA366.LPUART_SoftwareReset (*C function*), 739
drivers_MCX_MCXA_MCXA366.lpuart_stop_bit_count_t (*C type*), 756
drivers_MCX_MCXA_MCXA366.lpuart_transfer_callback_t (*C type*), 756
drivers_MCX_MCXA_MCXA366.lpuart_transfer_t (*C type*), 756
drivers_MCX_MCXA_MCXA366.LPUART_TransferAbortReceive (*C function*), 749
drivers_MCX_MCXA_MCXA366.LPUART_TransferAbortReceiveEDMA (*C function*), 762
drivers_MCX_MCXA_MCXA366.LPUART_TransferAbortSend (*C function*), 748
drivers_MCX_MCXA_MCXA366.LPUART_TransferAbortSendEDMA (*C function*), 761
drivers_MCX_MCXA_MCXA366.LPUART_TransferCreateHandle (*C function*), 747
drivers_MCX_MCXA_MCXA366.LPUART_TransferCreateHandleEDMA (*C function*), 760
drivers_MCX_MCXA_MCXA366.LPUART_TransferEdmaHandleIRQ (*C function*), 762
drivers_MCX_MCXA_MCXA366.LPUART_TransferEnable16Bit (*C function*), 742
drivers_MCX_MCXA_MCXA366.LPUART_TransferGetReceiveCount (*C function*), 750
drivers_MCX_MCXA_MCXA366.LPUART_TransferGetReceiveCountEDMA (*C function*), 762
drivers_MCX_MCXA_MCXA366.LPUART_TransferGetRxRingBufferLength (*C function*), 748
drivers_MCX_MCXA_MCXA366.LPUART_TransferGetSendCount (*C function*), 748
drivers_MCX_MCXA_MCXA366.LPUART_TransferGetSendCountEDMA (*C function*), 762
drivers_MCX_MCXA_MCXA366.LPUART_TransferHandleErrorIRQ (*C function*), 750
drivers_MCX_MCXA_MCXA366.LPUART_TransferHandleIRQ (*C function*), 750
drivers_MCX_MCXA_MCXA366.LPUART_TransferReceiveNonBlocking (*C function*), 749
drivers_MCX_MCXA_MCXA366.LPUART_TransferSendNonBlocking (*C function*), 747
drivers_MCX_MCXA_MCXA366.LPUART_TransferStartRingBuffer (*C function*), 748
drivers_MCX_MCXA_MCXA366.LPUART_TransferStopRingBuffer (*C function*), 748
drivers_MCX_MCXA_MCXA366.lpuart_transmit_cts_config_t (*C type*), 756
drivers_MCX_MCXA_MCXA366.lpuart_transmit_cts_source_t (*C type*), 756
drivers_MCX_MCXA_MCXA366.lpuart_transmit_rts_polarity_t (*C type*), 756
drivers_MCX_MCXA_MCXA366.LPUART_WriteBlocking (*C function*), 745
drivers_MCX_MCXA_MCXA366.LPUART_WriteBlocking16bit (*C function*), 746
drivers_MCX_MCXA_MCXA366.LPUART_WriteByte (*C function*), 744
drivers_MCX_MCXA_MCXA366.main_domain (*C var*), 782
drivers_MCX_MCXA_MCXA366.MAKE_STATUS (*C macro*), 630
drivers_MCX_MCXA_MCXA366.MAKE_VERSION (*C macro*), 630
drivers_MCX_MCXA_MCXA366.mau_config_t (*C type*), 768
drivers_MCX_MCXA_MCXA366.mau_data_type_t (*C type*), 767
drivers_MCX_MCXA_MCXA366.MAU_Deinit (*C function*), 766
drivers_MCX_MCXA_MCXA366.MAU_DT_SET (*C macro*), 768
drivers_MCX_MCXA_MCXA366.mau_flags_t (*C type*), 768
drivers_MCX_MCXA_MCXA366.MAU_INDIRECT_ADDR (*C macro*), 768
drivers_MCX_MCXA_MCXA366.MAU_Init (*C function*), 766
drivers_MCX_MCXA_MCXA366.MAU_MATH_PI (*C macro*), 768
drivers_MCX_MCXA_MCXA366.MAU_MOPC_SET (*C macro*), 768
drivers_MCX_MCXA_MCXA366.mau_mopc_t (*C type*), 767
drivers_MCX_MCXA_MCXA366.mau_q15_t (*C type*), 764
drivers_MCX_MCXA_MCXA366.mau_q31_t (*C type*), 764
drivers_MCX_MCXA_MCXA366.MAU_REG_FLOAT (*C macro*), 768
drivers_MCX_MCXA_MCXA366.MAU_REG_Q15 (*C macro*), 768
drivers_MCX_MCXA_MCXA366.MAU_REG_Q31 (*C macro*), 768
drivers_MCX_MCXA_MCXA366.MAU_REG_UINT32 (*C macro*), 768
drivers_MCX_MCXA_MCXA366.MAU_RES_SET (*C macro*), 768
drivers_MCX_MCXA_MCXA366.mau_result_t (*C type*), 767
drivers_MCX_MCXA_MCXA366.MAX (*C macro*), 615

drivers_MCX_MCXA_MCXA366.MCUX_DEPRECATED (*C macro*), 618
drivers_MCX_MCXA_MCXA366.MCUX_DEPRECATED_MACRO (*C macro*), 618
drivers_MCX_MCXA_MCXA366.MCUX_EXPERIMENTAL (*C macro*), 618
drivers_MCX_MCXA_MCXA366.MCUX_EXPERIMENTAL_MACRO (*C macro*), 618
drivers_MCX_MCXA_MCXA366.MCUX_MASK_INVERT_8 (*C macro*), 615
drivers_MCX_MCXA_MCXA366.MCUX_MASK_INVERT_16 (*C macro*), 615
drivers_MCX_MCXA_MCXA366.MCUX_MASK_INVERT_32 (*C macro*), 615
drivers_MCX_MCXA_MCXA366.MCUX_RAMFUNC (*C macro*), 618
drivers_MCX_MCXA_MCXA366.MCUX_REG_BIT_CLEAR8 (*C macro*), 616
drivers_MCX_MCXA_MCXA366.MCUX_REG_BIT_CLEAR16 (*C macro*), 616
drivers_MCX_MCXA_MCXA366.MCUX_REG_BIT_CLEAR32 (*C macro*), 616
drivers_MCX_MCXA_MCXA366.MCUX_REG_BIT_GET8 (*C macro*), 616
drivers_MCX_MCXA_MCXA366.MCUX_REG_BIT_GET16 (*C macro*), 616
drivers_MCX_MCXA_MCXA366.MCUX_REG_BIT_GET32 (*C macro*), 616
drivers_MCX_MCXA_MCXA366.MCUX_REG_BIT_SET8 (*C macro*), 616
drivers_MCX_MCXA_MCXA366.MCUX_REG_BIT_SET16 (*C macro*), 616
drivers_MCX_MCXA_MCXA366.MCUX_REG_BIT_SET32 (*C macro*), 616
drivers_MCX_MCXA_MCXA366.MCUX_REG_MODIFY8 (*C macro*), 616
drivers_MCX_MCXA_MCXA366.MCUX_REG_MODIFY16 (*C macro*), 616
drivers_MCX_MCXA_MCXA366.MCUX_REG_MODIFY32 (*C macro*), 616
drivers_MCX_MCXA_MCXA366.MCUX_REG_READ8 (*C macro*), 616
drivers_MCX_MCXA_MCXA366.MCUX_REG_READ16 (*C macro*), 616
drivers_MCX_MCXA_MCXA366.MCUX_REG_READ32 (*C macro*), 616
drivers_MCX_MCXA_MCXA366.MCUX_REG_WRITE8 (*C macro*), 615
drivers_MCX_MCXA_MCXA366.MCUX_REG_WRITE16 (*C macro*), 615
drivers_MCX_MCXA_MCXA366.MCUX_REG_WRITE32 (*C macro*), 616
drivers_MCX_MCXA_MCXA366.MIN (*C macro*), 615
drivers_MCX_MCXA_MCXA366.MSDK_HAS_DWT_CYCCNT (*C macro*), 630
drivers_MCX_MCXA_MCXA366.MSDK_INVALID_IRQ_HANDLER (*C macro*), 630
drivers_MCX_MCXA_MCXA366.MSDK_REG_NONSECURE_ADDR (*C macro*), 630
drivers_MCX_MCXA_MCXA366.MSDK_REG_SECURE_ADDR (*C macro*), 630
drivers_MCX_MCXA_MCXA366.MSEC_TO_COUNT (*C macro*), 617
drivers_MCX_MCXA_MCXA366.opamp_bias_current_t (*C type*), 847
drivers_MCX_MCXA_MCXA366.opamp_comp_cap_t (*C type*), 847
drivers_MCX_MCXA_MCXA366.opamp_config_t (*C type*), 847
drivers_MCX_MCXA_MCXA366.OPAMP_Deinit (*C function*), 846
drivers_MCX_MCXA_MCXA366.OPAMP_Enable (*C function*), 846
drivers_MCX_MCXA_MCXA366.OPAMP_GetDefaultConfig (*C function*), 846
drivers_MCX_MCXA_MCXA366.OPAMP_Init (*C function*), 846
drivers_MCX_MCXA_MCXA366.OPAMP_SetBiasCurrent (*C function*), 846
drivers_MCX_MCXA_MCXA366.OPAMP_SetCompensationCapcitor (*C function*), 846
drivers_MCX_MCXA_MCXA366.ostimer_callback_t (*C type*), 853
drivers_MCX_MCXA_MCXA366.OSTIMER_ClearStatusFlags (*C function*), 849
drivers_MCX_MCXA_MCXA366.OSTIMER_DecimalToGray (*C function*), 848
drivers_MCX_MCXA_MCXA366.OSTIMER_Deinit (*C function*), 848
drivers_MCX_MCXA_MCXA366.OSTIMER_DisableMatchInterrupt (*C function*), 851
drivers_MCX_MCXA_MCXA366.OSTIMER_DriverIRQHandler (*C function*), 852
drivers_MCX_MCXA_MCXA366.OSTIMER_EnableMatchInterrupt (*C function*), 851
drivers_MCX_MCXA_MCXA366.OSTIMER_GetCaptureRawValue (*C function*), 852
drivers_MCX_MCXA_MCXA366.OSTIMER_GetCaptureValue (*C function*), 852
drivers_MCX_MCXA_MCXA366.OSTIMER_GetCurrentTimerRawValue (*C function*), 851
drivers_MCX_MCXA_MCXA366.OSTIMER_GetCurrentTimerValue (*C function*), 852
drivers_MCX_MCXA_MCXA366.OSTIMER_GetMatchRegister (*C function*), 851
drivers_MCX_MCXA_MCXA366.OSTIMER_GetMatchValue (*C function*), 851
drivers_MCX_MCXA_MCXA366.OSTIMER_GetStatusFlags (*C function*), 848
drivers_MCX_MCXA_MCXA366.OSTIMER_GrayToDecimal (*C function*), 848
drivers_MCX_MCXA_MCXA366.OSTIMER_HandleIRQ (*C function*), 852
drivers_MCX_MCXA_MCXA366.OSTIMER_Init (*C function*), 848

drivers_MCX_MCXA_MCXA366.OSTIMER_SetMatchRawValue (*C function*), 849
drivers_MCX_MCXA_MCXA366.OSTIMER_SetMatchRegister (*C function*), 850
drivers_MCX_MCXA_MCXA366.OSTIMER_SetMatchValue (*C function*), 849
drivers_MCX_MCXA_MCXA366.OSTIMER_SetMatchValueSafe (*C function*), 849
drivers_MCX_MCXA_MCXA366.p_buffer (*C var*), 915
drivers_MCX_MCXA_MCXA366.p_buffer_ping_pong (*C var*), 915
drivers_MCX_MCXA_MCXA366.p_gpio_reg (*C var*), 916
drivers_MCX_MCXA_MCXA366.p_keycan_interval (*C var*), 916
drivers_MCX_MCXA_MCXA366.p_keyvalue (*C var*), 916
drivers_MCX_MCXA_MCXA366.p_stripe_index (*C var*), 915
drivers_MCX_MCXA_MCXA366.pCos (*C var*), 764
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kDAC_FIFOEmptyDMAEnable (*C enumerator*), 226
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kDAC_FIFOEmptyFlag (*C enumerator*), 226
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kDAC_FIFOEmptyInterruptEnable (*C enumerator*), 225
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kDAC_FIFOFullFlag (*C enumerator*), 227
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kDAC_FIFOFullInterruptEnable (*C enumerator*), 225
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kDAC_FIFOOverflowFlag (*C enumerator*), 226
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kDAC_FIFOOverflowInterruptEnable (*C enumerator*), 226
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kDAC_FIFOSwingBackFlag (*C enumerator*), 226
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kDAC_FIFOUnderflowFlag (*C enumerator*), 226
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kDAC_FIFOUnderflowInterruptEnable (*C enumerator*), 226
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kDAC_FIFOWatermarkDMAEnable (*C enumerator*), 226
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kDAC_FIFOWatermarkFlag (*C enumerator*), 226
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kDAC_FIFOWatermarkInterruptEnable (*C enumerator*), 225
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kDAC_PeriodTriggerCompleteFlag (*C enumerator*), 227
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kDAC_PeriodTriggerCompleteInterruptEnable (*C enumerator*), 226
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kDAC_ResetFIFO (*C enumerator*), 225
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kDAC_ResetLogic (*C enumerator*), 225
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kDAC_SwingBackInterruptEnable (*C enumerator*), 225
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_DestinationAddressErrorFlag (*C enumerator*), 253
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_DestinationBusErrorFlag (*C enumerator*), 253
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_DestinationOffsetErrorFlag (*C enumerator*), 253
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_DoneFlag (*C enumerator*), 252
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_ErrorChannelFlag (*C enumerator*), 253
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_ErrorFlag (*C enumerator*), 253
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_ErrorInterruptEnable (*C enumerator*), 253
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_HalfInterruptEnable (*C enumer-*

ator), 254
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_InterruptFlag (*C enumerator*), 253
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_MajorInterruptEnable (*C enumerator*), 254
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_MasterId (*C enumerator*), 256
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_NbytesErrorFlag (*C enumerator*), 253
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_PrivilegedAccessLevel (*C enumerator*), 256
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_ScatterGatherErrorFlag (*C enumerator*), 253
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_SourceAddressErrorFlag (*C enumerator*), 253
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_SourceBusErrorFlag (*C enumerator*), 253
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_SourceOffsetErrorFlag (*C enumerator*), 253
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_TransferCanceledFlag (*C enumerator*), 253
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kEDMA_ValidFlag (*C enumerator*), 253
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kERM_AllInterruptsEnable (*C enumerator*), 294
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kERM_AllIntsFlag (*C enumerator*), 294
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kERM_NonCorrectableErrorIntFlag (*C enumerator*), 294
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kERM_NonCorrectableIntEnable (*C enumerator*), 294
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kERM_SingleBitCorrectionIntFlag (*C enumerator*), 294
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kERM_SingleCorrectionIntEnable (*C enumerator*), 294
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kFLEXCAN_RxFifoFrameAvlFlag (*C enumerator*), 327
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kFLEXCAN_RxFifoOverflowFlag (*C enumerator*), 327
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kFLEXCAN_RxFifoWarningFlag (*C enumerator*), 327
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kFLEXIO_I2S_RxDataRegFullFlag (*C enumerator*), 423
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kFLEXIO_I2S_RxDataRegFullInterruptEnable (*C enumerator*), 423
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kFLEXIO_I2S_TxDataRegEmptyFlag (*C enumerator*), 423
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kFLEXIO_I2S_TxDataRegEmptyInterruptEnable (*C enumerator*), 422
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_Busy (*C enumerator*), 627
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_EDMA_Busy (*C enumerator*), 249
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_EDMA_QueueFull (*C enumerator*), 249
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_Fail (*C enumerator*), 627
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXCAN_ErrorStatus (*C enumerator*), 317
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXCAN_MemoryError (*C enumerator*), 317
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXCAN_RxBusy (*C enumerator*), 316

drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXCAN_RxFifoBusy (*C enumerator*), 316
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXCAN_RxFifoDisabled (*C enumerator*), 317
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXCAN_RxFifoIdle (*C enumerator*), 316
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXCAN_RxFifoOverflow (*C enumerator*), 317
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXCAN_RxFifoUnderflow (*C enumerator*), 317
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXCAN_RxFifoWarning (*C enumerator*), 317
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXCAN_RxIdle (*C enumerator*), 316
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXCAN_RxOverflow (*C enumerator*), 316
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXCAN_RxRemote (*C enumerator*), 317
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXCAN_TxBusy (*C enumerator*), 316
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXCAN_TxIdle (*C enumerator*), 316
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXCAN_TxSwitchToRx (*C enumerator*), 316
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXCAN_UnHandled (*C enumerator*), 317
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXCAN_WakeUp (*C enumerator*), 317
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_A_FORMAT_BaudrateNotSupport (*C enumerator*), 354
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_A_FORMAT_FrameErr (*C enumerator*), 354
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_A_FORMAT_NotSyncCMD (*C enumerator*), 354
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_A_FORMAT_OutOfIDRange (*C enumerator*), 354
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_A_FORMAT_RxBusy (*C enumerator*), 353
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_A_FORMAT_RxHardwareOverrun (*C enumerator*), 354
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_A_FORMAT_RxIdle (*C enumerator*), 353
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_A_FORMAT_RxRingBufferOverrun (*C enumerator*), 354
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_A_FORMAT_Timeout (*C enumerator*), 354
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_A_FORMAT_TxBusy (*C enumerator*), 353
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_A_FORMAT_TxIdle (*C enumerator*), 353
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_CAMERA_RxBusy (*C enumerator*), 371
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_CAMERA_RxIdle (*C enumerator*), 371
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_I2C_Busy (*C enumerator*), 412
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_I2C_Idle (*C enumerator*), 412

drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_I2C_Nak (*C enumerator*), 412
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_I2C_Timeout (*C enumerator*), 412
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_I2S_Error (*C enumerator*), 422
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_I2S_Idle (*C enumerator*), 422
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_I2S_QueueFull (*C enumerator*), 422
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_I2S_RxBusy (*C enumerator*), 422
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_I2S_Timeout (*C enumerator*), 422
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_I2S_TxBusy (*C enumerator*), 422
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_MCULCD_Busy (*C enumerator*), 435
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_MCULCD_Error (*C enumerator*), 435
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_MCULCD_Idle (*C enumerator*), 435
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_SPI_Busy (*C enumerator*), 451
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_SPI_Error (*C enumerator*), 451
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_SPI_Idle (*C enumerator*), 451
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_SPI_Timeout (*C enumerator*), 451
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_BaudrateNotSupport (*C enumerator*), 458
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_ComAlr0_ParityErr (*C enumerator*), 457
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_ComAlr1_DelimiterErr (*C enumerator*), 458
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_EncErr0_CountingErr (*C enumerator*), 457
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_EncErr1_LogicOR (*C enumerator*), 457
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_EncErr_BA (*C enumerator*), 458
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_EncErr_BE (*C enumerator*), 458
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_EncErr_CE (*C enumerator*), 458
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_EncErr_FS (*C enumerator*), 458
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_EncErr_ME (*C enumerator*), 458
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_EncErr_OF (*C enumerator*), 458
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_EncErr_OH (*C enumerator*), 458
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_EncErr_OS (*C enumerator*), 458
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_FrameErr (*C enumerator*), 458

drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_RxBusy (*C enumerator*), 458
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_RxHardwareOverrun (*C enumerator*), 459
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_RxIdle (*C enumerator*), 458
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_RxRingBufferOverrun (*C enumerator*), 458
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_Timeout (*C enumerator*), 458
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_TxBusy (*C enumerator*), 458
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_T_FORMAT_TxIdle (*C enumerator*), 458
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_UART_BaudrateNotSupport (*C enumerator*), 478
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_UART_ERROR (*C enumerator*), 478
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_UART_RxBusy (*C enumerator*), 478
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_UART_RxHardwareOverrun (*C enumerator*), 478
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_UART_RxIdle (*C enumerator*), 478
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_UART_RxRingBufferOverrun (*C enumerator*), 478
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_UART_Timeout (*C enumerator*), 478
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_UART_TxBusy (*C enumerator*), 478
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_FLEXIO_UART_TxIdle (*C enumerator*), 478
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_GLIKEY_DisabledError (*C enumerator*), 542
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_GLIKEY_Locked (*C enumerator*), 542
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_GLIKEY_LockedError (*C enumerator*), 542
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_GLIKEY_NotLocked (*C enumerator*), 542
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_Busy (*C enumerator*), 556
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_CrcError (*C enumerator*), 556
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_HdrParityError (*C enumerator*), 556
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_IBIWon (*C enumerator*), 556
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_Idle (*C enumerator*), 556
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_InvalidReq (*C enumerator*), 556
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_InvalidStart (*C enumerator*), 557
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_MsgError (*C enumerator*), 556
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_Nak (*C enumerator*), 556
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_OverrunError (*C enumerator*), 557
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_ReadFifoError (*C enumera-*

tor), 556
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_S0S1Error (*C enumerator*), 557
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_SdrParityError (*C enumerator*), 557
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_SlaveCountExceed (*C enumerator*), 556
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_Term (*C enumerator*), 556
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_Timeout (*C enumerator*), 556
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_UnderrunError (*C enumerator*), 557
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_UnderrunNak (*C enumerator*), 557
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_WriteAbort (*C enumerator*), 556
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_I3C_WriteFifoError (*C enumerator*), 556
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_InvalidArgument (*C enumerator*), 627
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPI2C_ArbitrationLost (*C enumerator*), 670
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPI2C_BitError (*C enumerator*), 670
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPI2C_Busy (*C enumerator*), 670
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPI2C_DmaRequestFail (*C enumerator*), 670
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPI2C_FifoError (*C enumerator*), 670
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPI2C_Idle (*C enumerator*), 670
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPI2C_Nak (*C enumerator*), 670
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPI2C_NoTransferInProgress (*C enumerator*), 670
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPI2C_PinLowTimeout (*C enumerator*), 670
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPI2C_Timeout (*C enumerator*), 671
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPSPI_Busy (*C enumerator*), 711
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPSPI_Error (*C enumerator*), 711
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPSPI_Idle (*C enumerator*), 711
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPSPI_OutOfRange (*C enumerator*), 712
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPSPI_Timeout (*C enumerator*), 712
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPUART_BaudrateNotSupport (*C enumerator*), 751
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPUART_Error (*C enumerator*), 751
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPUART_FlagCannotClearManually (*C enumerator*), 751
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPUART_FramingError (*C enumerator*), 751
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPUART_IdleLineDetected (*C enumerator*), 751
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPUART_NoiseError (*C enu-*

merator), 751
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPUART_ParityError (*C enumerator*), 751
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPUART_RxBusy (*C enumerator*), 750
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPUART_RxHardwareOverrun (*C enumerator*), 751
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPUART_RxIdle (*C enumerator*), 751
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPUART_RxRingBufferOverrun (*C enumerator*), 751
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPUART_RxWatermarkTooLarge (*C enumerator*), 751
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPUART_Timeout (*C enumerator*), 751
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPUART_TxBusy (*C enumerator*), 750
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPUART_TxIdle (*C enumerator*), 750
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_LPUART_TxWatermarkTooLarge (*C enumerator*), 751
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_NoData (*C enumerator*), 627
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_NoTransferInProgress (*C enumerator*), 627
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_OutOfRange (*C enumerator*), 627
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_ReadOnly (*C enumerator*), 627
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_SPC_BandgapModeWrong (*C enumerator*), 810
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_SPC_Busy (*C enumerator*), 810
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_SPC_CORELDOLowDriveStrengthIgnore (*C enumerator*), 810
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_SPC_CORELDOVoltageDetectWrong (*C enumerator*), 810
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_SPC_CORELDOVoltageSetFail (*C enumerator*), 810
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_SPC_CORELDOVoltageWrong (*C enumerator*), 810
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_SPC_DCDCCoreLdoVoltageMisMatch (*C enumerator*), 810
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_SPC_DCDCLowDriveStrengthIgnore (*C enumerator*), 810
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_SPC_DCDCPulseRefreshModeIgnore (*C enumerator*), 810
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_SPC_SYSLDOLowDriveStrengthIgnore (*C enumerator*), 810
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_SPC_SYSLDOOverDriveVoltageFail (*C enumerator*), 810
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_Success (*C enumerator*), 627
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_Timeout (*C enumerator*), 627
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_VBAT_BandgapNotEnabled (*C enumerator*), 824
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_VBAT_ClockMonitorLocked (*C enumerator*), 824
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_VBAT_Fro16kNotEnabled (*C enumerator*), 824
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_VBAT_LDONotReady (*C enumerator*), 824

drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_VBAT_OSC32KNotReady (*C enumerator*), 824
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_VBAT_TamperLocked (*C enumerator*), 824
drivers_MCX_MCXA_MCXA366.PhonyNameDueToError.kStatus_VBAT_WrongCapacitanceValue (*C enumerator*), 824
drivers_MCX_MCXA_MCXA366.PORT_ClearAllHighEFTDetectors (*C function*), 856
drivers_MCX_MCXA_MCXA366.PORT_ClearAllLowEFTDetectors (*C function*), 856
drivers_MCX_MCXA_MCXA366.port_digital_filter_clock_source_t (*C type*), 860
drivers_MCX_MCXA_MCXA366.port_digital_filter_config_t (*C type*), 860
drivers_MCX_MCXA_MCXA366.PORT_DisableEFTDetectInterrupts (*C function*), 856
drivers_MCX_MCXA_MCXA366.PORT_EnableEFTDetectInterrupts (*C function*), 856
drivers_MCX_MCXA_MCXA366.PORT_EnablePinDoubleDriveStrength (*C function*), 855
drivers_MCX_MCXA_MCXA366.PORT_EnablePinsDigitalFilter (*C function*), 854
drivers_MCX_MCXA_MCXA366.PORT_GetEFTDetectFlags (*C function*), 855
drivers_MCX_MCXA_MCXA366.PORT_GetVersionInfo (*C function*), 853
drivers_MCX_MCXA_MCXA366.port_mux_t (*C type*), 860
drivers_MCX_MCXA_MCXA366.port_pin_config_t (*C type*), 860
drivers_MCX_MCXA_MCXA366.PORT_SecletPortVoltageRange (*C function*), 853
drivers_MCX_MCXA_MCXA366.PORT_SetDigitalFilterConfig (*C function*), 855
drivers_MCX_MCXA_MCXA366.PORT_SetMultiplePinsConfig (*C function*), 854
drivers_MCX_MCXA_MCXA366.PORT_SetPinConfig (*C function*), 853
drivers_MCX_MCXA_MCXA366.PORT_SetPinDriveStrength (*C function*), 855
drivers_MCX_MCXA_MCXA366.PORT_SetPinMux (*C function*), 854
drivers_MCX_MCXA_MCXA366.PORT_SetPinPullValue (*C function*), 855
drivers_MCX_MCXA_MCXA366.port_version_info_t (*C type*), 860
drivers_MCX_MCXA_MCXA366.port_voltage_range_t (*C type*), 860
drivers_MCX_MCXA_MCXA366.pSin (*C var*), 764
drivers_MCX_MCXA_MCXA366.PWM_ActivateOutputTrigger (*C function*), 884
drivers_MCX_MCXA_MCXA366.pwm_channels_t (*C type*), 879
drivers_MCX_MCXA_MCXA366.pwm_chnl_pair_operation_t (*C type*), 880
drivers_MCX_MCXA_MCXA366.PWM_ClearStatusFlags (*C function*), 866
drivers_MCX_MCXA_MCXA366.pwm_clock_prescale_t (*C type*), 879
drivers_MCX_MCXA_MCXA366.pwm_clock_source_t (*C type*), 879
drivers_MCX_MCXA_MCXA366.pwm_config_t (*C type*), 881
drivers_MCX_MCXA_MCXA366.PWM_DeactivateOutputTrigger (*C function*), 885
drivers_MCX_MCXA_MCXA366.PWM_Deinit (*C function*), 862
drivers_MCX_MCXA_MCXA366.PWM_DisableInterrupts (*C function*), 865
drivers_MCX_MCXA_MCXA366.pwm_dma_enable_t (*C type*), 880
drivers_MCX_MCXA_MCXA366.pwm_dma_source_select_t (*C type*), 880
drivers_MCX_MCXA_MCXA366.PWM_DMACaptureSourceSelect (*C function*), 866
drivers_MCX_MCXA_MCXA366.PWM_DMAFIFOWatermarkControl (*C function*), 865
drivers_MCX_MCXA_MCXA366.PWM_EnableDMACapture (*C function*), 866
drivers_MCX_MCXA_MCXA366.PWM_EnableDMAWrite (*C function*), 866
drivers_MCX_MCXA_MCXA366.PWM_EnableInterrupts (*C function*), 865
drivers_MCX_MCXA_MCXA366.PWM_EnableLocalForce (*C function*), 883
drivers_MCX_MCXA_MCXA366.pwm_fault_channels_t (*C type*), 880
drivers_MCX_MCXA_MCXA366.pwm_fault_clear_t (*C type*), 881
drivers_MCX_MCXA_MCXA366.pwm_fault_disable_t (*C type*), 880
drivers_MCX_MCXA_MCXA366.pwm_fault_input_filter_param_t (*C type*), 881
drivers_MCX_MCXA_MCXA366.pwm_fault_input_t (*C type*), 880
drivers_MCX_MCXA_MCXA366.pwm_fault_param_t (*C type*), 881
drivers_MCX_MCXA_MCXA366.pwm_fault_recovery_mode_t (*C type*), 880
drivers_MCX_MCXA_MCXA366.pwm_fault_state_t (*C type*), 881
drivers_MCX_MCXA_MCXA366.PWM_FaultDefaultConfig (*C function*), 883
drivers_MCX_MCXA_MCXA366.pwm_force_output_trigger_t (*C type*), 880
drivers_MCX_MCXA_MCXA366.pwm_force_signal_t (*C type*), 880
drivers_MCX_MCXA_MCXA366.PWM_GetDefaultConfig (*C function*), 862

drivers_MCX_MCXA_MCXA366.PWM_GetEnabledInterrupts (*C function*), 865
drivers_MCX_MCXA_MCXA366.PWM_GetInputCaptureValue (*C function*), 882
drivers_MCX_MCXA_MCXA366.PWM_GetPwmChannelState (*C function*), 887
drivers_MCX_MCXA_MCXA366.PWM_GetStatusFlags (*C function*), 866
drivers_MCX_MCXA_MCXA366.PWM_GetVALxValue (*C function*), 884
drivers_MCX_MCXA_MCXA366.PWM_Init (*C function*), 862
drivers_MCX_MCXA_MCXA366.pwm_init_source_t (*C type*), 880
drivers_MCX_MCXA_MCXA366.pwm_input_capture_edge_t (*C type*), 880
drivers_MCX_MCXA_MCXA366.pwm_input_capture_param_t (*C type*), 881
drivers_MCX_MCXA_MCXA366.pwm_interrupt_enable_t (*C type*), 880
drivers_MCX_MCXA_MCXA366.pwm_level_select_t (*C type*), 881
drivers_MCX_MCXA_MCXA366.pwm_load_frequency_t (*C type*), 880
drivers_MCX_MCXA_MCXA366.pwm_mode_t (*C type*), 881
drivers_MCX_MCXA_MCXA366.pwm_module_control_t (*C type*), 881
drivers_MCX_MCXA_MCXA366.pwm_output_state_t (*C type*), 880
drivers_MCX_MCXA_MCXA366.PWM_OutputDisable (*C function*), 886
drivers_MCX_MCXA_MCXA366.PWM_OutputEnable (*C function*), 886
drivers_MCX_MCXA_MCXA366.PWM_OutputTriggerEnable (*C function*), 884
drivers_MCX_MCXA_MCXA366.pwm_register_reload_t (*C type*), 880
drivers_MCX_MCXA_MCXA366.pwm_reload_source_select_t (*C type*), 881
drivers_MCX_MCXA_MCXA366.PWM_SetChannelOutput (*C function*), 887
drivers_MCX_MCXA_MCXA366.PWM_SetClockMode (*C function*), 887
drivers_MCX_MCXA_MCXA366.PWM_SetFilterSampleCount (*C function*), 888
drivers_MCX_MCXA_MCXA366.PWM_SetFilterSamplePeriod (*C function*), 888
drivers_MCX_MCXA_MCXA366.PWM_SetOutputToIdle (*C function*), 887
drivers_MCX_MCXA_MCXA366.PWM_SetPhaseDelay (*C function*), 888
drivers_MCX_MCXA_MCXA366.PWM_SetPwmFaultState (*C function*), 885
drivers_MCX_MCXA_MCXA366.PWM_SetPwmForceOutputToZero (*C function*), 887
drivers_MCX_MCXA_MCXA366.PWM_SetPwmLdok (*C function*), 885
drivers_MCX_MCXA_MCXA366.PWM_SetupFaultDisableMap (*C function*), 886
drivers_MCX_MCXA_MCXA366.PWM_SetupFaultInputFilter (*C function*), 882
drivers_MCX_MCXA_MCXA366.PWM_SetupFaultInputFilterExt (*C function*), 882
drivers_MCX_MCXA_MCXA366.PWM_SetupFaults (*C function*), 882
drivers_MCX_MCXA_MCXA366.PWM_SetupFaultsExt (*C function*), 882
drivers_MCX_MCXA_MCXA366.PWM_SetupForceSignal (*C function*), 883
drivers_MCX_MCXA_MCXA366.PWM_SetupInputCapture (*C function*), 881
drivers_MCX_MCXA_MCXA366.PWM_SetupPwm (*C function*), 863
drivers_MCX_MCXA_MCXA366.PWM_SetupPwmPhaseShift (*C function*), 863
drivers_MCX_MCXA_MCXA366.PWM_SetupSwCtrlOut (*C function*), 885
drivers_MCX_MCXA_MCXA366.PWM_SetVALxValue (*C function*), 884
drivers_MCX_MCXA_MCXA366.pwm_signal_param_t (*C type*), 881
drivers_MCX_MCXA_MCXA366.PWM_StartTimer (*C function*), 867
drivers_MCX_MCXA_MCXA366.pwm_status_flags_t (*C type*), 880
drivers_MCX_MCXA_MCXA366.PWM_StopTimer (*C function*), 867
drivers_MCX_MCXA_MCXA366.PWM_SUBMODULE_CHANNEL (*C macro*), 888
drivers_MCX_MCXA_MCXA366.PWM_SUBMODULE_SWCONTROL_WIDTH (*C macro*), 888
drivers_MCX_MCXA_MCXA366.pwm_submodule_t (*C type*), 879
drivers_MCX_MCXA_MCXA366.PWM_UpdateCurrentPolarity (*C function*), 883
drivers_MCX_MCXA_MCXA366.PWM_UpdatePwmDutycycle (*C function*), 864
drivers_MCX_MCXA_MCXA366.PWM_UpdatePwmDutycycleHighAccuracy (*C function*), 864
drivers_MCX_MCXA_MCXA366.PWM_UpdatePwmPeriodAndDutycycle (*C function*), 864
drivers_MCX_MCXA_MCXA366.pwm_value_register_t (*C type*), 879
drivers_MCX_MCXA_MCXA366.pwm_watermark_control_t (*C type*), 881
drivers_MCX_MCXA_MCXA366.RAMFUNCTION_SECTION_CODE (*C macro*), 618
drivers_MCX_MCXA_MCXA366.resetFilterEnable (*C var*), 782
drivers_MCX_MCXA_MCXA366.resetFilterWidth (*C var*), 782
drivers_MCX_MCXA_MCXA366.RTC_ClearStatusFlags (*C function*), 893
drivers_MCX_MCXA_MCXA366.rtc_config_t (*C type*), 897

drivers_MCX_MCXA_MCXA366.rtc_datetime_t (*C type*), 897
drivers_MCX_MCXA_MCXA366.RTC_Deinit (*C function*), 891
drivers_MCX_MCXA_MCXA366.RTC_DisableInterrupts (*C function*), 893
drivers_MCX_MCXA_MCXA366.RTC_EnableClockOutput (*C function*), 898
drivers_MCX_MCXA_MCXA366.RTC_EnableInterrupts (*C function*), 893
drivers_MCX_MCXA_MCXA366.RTC_EnableLPOClock (*C function*), 893
drivers_MCX_MCXA_MCXA366.RTC_EnableWakeUpPin (*C function*), 897
drivers_MCX_MCXA_MCXA366.RTC_GetAlarm (*C function*), 892
drivers_MCX_MCXA_MCXA366.RTC_GetDatetime (*C function*), 892
drivers_MCX_MCXA_MCXA366.RTC_GetDefaultConfig (*C function*), 891
drivers_MCX_MCXA_MCXA366.RTC_GetEnabledInterrupts (*C function*), 893
drivers_MCX_MCXA_MCXA366.RTC_GetMonotonicCounter (*C function*), 894
drivers_MCX_MCXA_MCXA366.RTC_GetStatusFlags (*C function*), 893
drivers_MCX_MCXA_MCXA366.RTC_GetTamperTimeSeconds (*C function*), 897
drivers_MCX_MCXA_MCXA366.RTC_IncrementMonotonicCounter (*C function*), 894
drivers_MCX_MCXA_MCXA366.RTC_Init (*C function*), 891
drivers_MCX_MCXA_MCXA366.rtc_interrupt_enable_t (*C type*), 896
drivers_MCX_MCXA_MCXA366.rtc_osc_cap_load_t (*C type*), 897
drivers_MCX_MCXA_MCXA366.rtc_pin_config_t (*C type*), 897
drivers_MCX_MCXA_MCXA366.RTC_Reset (*C function*), 897
drivers_MCX_MCXA_MCXA366.RTC_SetAlarm (*C function*), 892
drivers_MCX_MCXA_MCXA366.RTC_SetDatetime (*C function*), 892
drivers_MCX_MCXA_MCXA366.RTC_SetMonotonicCounter (*C function*), 894
drivers_MCX_MCXA_MCXA366.RTC_SetOscCapLoad (*C function*), 897
drivers_MCX_MCXA_MCXA366.RTC_SetTimerSecondsInterruptFrequency (*C function*), 898
drivers_MCX_MCXA_MCXA366.RTC_StartTimer (*C function*), 893
drivers_MCX_MCXA_MCXA366.rtc_status_flags_t (*C type*), 897
drivers_MCX_MCXA_MCXA366.RTC_StopTimer (*C function*), 894
drivers_MCX_MCXA_MCXA366.rtc_timer_seconds_interrupt_frequency_t (*C type*), 897
drivers_MCX_MCXA_MCXA366.RTR_EXT (*C macro*), 334
drivers_MCX_MCXA_MCXA366.RTR_STD_HIGH (*C macro*), 334
drivers_MCX_MCXA_MCXA366.RTR_STD_LOW (*C macro*), 334
drivers_MCX_MCXA_MCXA366.rxData (*C var*), 367, 368, 469
drivers_MCX_MCXA_MCXA366.rxDataSize (*C var*), 368, 470
drivers_MCX_MCXA_MCXA366.rxDataSizeAll (*C var*), 368, 470
drivers_MCX_MCXA_MCXA366.RxPinIndex (*C var*), 367, 468
drivers_MCX_MCXA_MCXA366.rxRingBuffer (*C var*), 368, 470
drivers_MCX_MCXA_MCXA366.rxRingBufferHead (*C var*), 368, 470
drivers_MCX_MCXA_MCXA366.rxRingBufferSize (*C var*), 368, 470
drivers_MCX_MCXA_MCXA366.rxRingBufferTail (*C var*), 368, 470
drivers_MCX_MCXA_MCXA366.rxState (*C var*), 368, 470
drivers_MCX_MCXA_MCXA366.s_flexioBases (*C var*), 389
drivers_MCX_MCXA_MCXA366.s_flexioClocks (*C var*), 389
drivers_MCX_MCXA_MCXA366.s_lpi2cMasterHandle (*C var*), 671
drivers_MCX_MCXA_MCXA366.s_lpi2cMasterIsr (*C var*), 671
drivers_MCX_MCXA_MCXA366.s_lpuartHandle (*C var*), 757
drivers_MCX_MCXA_MCXA366.s_lpuartIsr (*C var*), 757
drivers_MCX_MCXA_MCXA366.s_lpuartTxIRQ (*C var*), 757
drivers_MCX_MCXA_MCXA366.s_smartdmaCameraFirmware (*C var*), 914
drivers_MCX_MCXA_MCXA366.s_smartdmaCameraFirmwareSize (*C var*), 914
drivers_MCX_MCXA_MCXA366.s_smartdmaDisplayFirmware (*C var*), 914
drivers_MCX_MCXA_MCXA366.s_smartdmaDisplayFirmwareSize (*C var*), 914
drivers_MCX_MCXA_MCXA366.s_smartdmaKeyscanFirmware (*C var*), 914
drivers_MCX_MCXA_MCXA366.s_smartdmaKeyscanFirmwareSize (*C var*), 915
drivers_MCX_MCXA_MCXA366.SC_ADD (*C macro*), 209
drivers_MCX_MCXA_MCXA366.SC_ADD1 (*C macro*), 209
drivers_MCX_MCXA_MCXA366.SC_ADD16 (*C macro*), 209
drivers_MCX_MCXA_MCXA366.SC_ADD256 (*C macro*), 209

drivers_MCX_MCXA_MCXA366.SC_CHECK (*C macro*), 209
drivers_MCX_MCXA_MCXA366.SC_SUB (*C macro*), 209
drivers_MCX_MCXA_MCXA366.SC_SUB1 (*C macro*), 209
drivers_MCX_MCXA_MCXA366.SC_SUB16 (*C macro*), 209
drivers_MCX_MCXA_MCXA366.SC_SUB256 (*C macro*), 209
drivers_MCX_MCXA_MCXA366.SDK_ALIGN (*C macro*), 617
drivers_MCX_MCXA_MCXA366.SDK_ATOMIC_LOCAL_ADD (*C macro*), 616
drivers_MCX_MCXA_MCXA366.SDK_ATOMIC_LOCAL_CLEAR (*C macro*), 616
drivers_MCX_MCXA_MCXA366.SDK_ATOMIC_LOCAL_CLEAR_AND_SET (*C macro*), 617
drivers_MCX_MCXA_MCXA366.SDK_ATOMIC_LOCAL_COMPARE_AND_SET (*C macro*), 617
drivers_MCX_MCXA_MCXA366.SDK_ATOMIC_LOCAL_SET (*C macro*), 616
drivers_MCX_MCXA_MCXA366.SDK_ATOMIC_LOCAL_SUB (*C macro*), 616
drivers_MCX_MCXA_MCXA366.SDK_ATOMIC_LOCAL_TEST_AND_SET (*C macro*), 617
drivers_MCX_MCXA_MCXA366.SDK_ATOMIC_LOCAL_TOGGLE (*C macro*), 616
drivers_MCX_MCXA_MCXA366.SDK_DelayAtLeastUs (*C function*), 628
drivers_MCX_MCXA_MCXA366.SDK_Free (*C function*), 628
drivers_MCX_MCXA_MCXA366.SDK_IS_ALIGNED (*C macro*), 617
drivers_MCX_MCXA_MCXA366.SDK_ISR_EXIT_BARRIER (*C macro*), 617
drivers_MCX_MCXA_MCXA366.SDK_Malloc (*C function*), 627
drivers_MCX_MCXA_MCXA366.SDK_SIZEALIGN (*C macro*), 617
drivers_MCX_MCXA_MCXA366.SDK_SIZEALIGN_DOWN (*C macro*), 617
drivers_MCX_MCXA_MCXA366.SDK_SIZEALIGN_UP (*C macro*), 617
drivers_MCX_MCXA_MCXA366.secure_counter_t (*C type*), 209
drivers_MCX_MCXA_MCXA366.shifterIndex (*C var*), 367, 469
drivers_MCX_MCXA_MCXA366.slcd_blink_mode_t (*C type*), 909
drivers_MCX_MCXA_MCXA366.slcd_blink_rate_t (*C type*), 909
drivers_MCX_MCXA_MCXA366.SLCD_ClearInterruptStatus (*C function*), 903
drivers_MCX_MCXA_MCXA366.slcd_clock_prescaler_t (*C type*), 909
drivers_MCX_MCXA_MCXA366.slcd_config_t (*C type*), 910
drivers_MCX_MCXA_MCXA366.SLCD_Deinit (*C function*), 900
drivers_MCX_MCXA_MCXA366.SLCD_DisableInterrupts (*C function*), 902
drivers_MCX_MCXA_MCXA366.slcd_display_mode_t (*C type*), 909
drivers_MCX_MCXA_MCXA366.slcd_duty_cycle_t (*C type*), 909
drivers_MCX_MCXA_MCXA366.SLCD_EnableInterrupts (*C function*), 902
drivers_MCX_MCXA_MCXA366.SLCD_EnablePadSafeState (*C function*), 902
drivers_MCX_MCXA_MCXA366.slcd_fault_detect_clock_prescaler_t (*C type*), 909
drivers_MCX_MCXA_MCXA366.slcd_fault_detect_config_t (*C type*), 910
drivers_MCX_MCXA_MCXA366.slcd_fault_detect_sample_window_width_t (*C type*), 909
drivers_MCX_MCXA_MCXA366.SLCD_GetDefaultConfig (*C function*), 900
drivers_MCX_MCXA_MCXA366.SLCD_GetFaultDetectCounter (*C function*), 902
drivers_MCX_MCXA_MCXA366.SLCD_GetInterruptStatus (*C function*), 903
drivers_MCX_MCXA_MCXA366.SLCD_Init (*C function*), 900
drivers_MCX_MCXA_MCXA366.slcd_interrupt_enable_t (*C type*), 909
drivers_MCX_MCXA_MCXA366.slcd_lowpower_behavior (*C type*), 909
drivers_MCX_MCXA_MCXA366.slcd_phase_index_t (*C type*), 909
drivers_MCX_MCXA_MCXA366.slcd_phase_type_t (*C type*), 909
drivers_MCX_MCXA_MCXA366.slcd_regulated_voltage_trim_t (*C type*), 909
drivers_MCX_MCXA_MCXA366.slcd_sample_hold_t (*C type*), 909
drivers_MCX_MCXA_MCXA366.SLCD_SetBackPlanePhase (*C function*), 901
drivers_MCX_MCXA_MCXA366.SLCD_SetFrontPlaneOnePhase (*C function*), 901
drivers_MCX_MCXA_MCXA366.SLCD_SetFrontPlaneSegments (*C function*), 901
drivers_MCX_MCXA_MCXA366.SLCD_StartBlinkMode (*C function*), 900
drivers_MCX_MCXA_MCXA366.SLCD_StartDisplay (*C function*), 900
drivers_MCX_MCXA_MCXA366.SLCD_StopBlinkMode (*C function*), 901
drivers_MCX_MCXA_MCXA366.SLCD_StopDisplay (*C function*), 900
drivers_MCX_MCXA_MCXA366.SMARTDMA_AccessShareRAM (*C function*), 913
drivers_MCX_MCXA_MCXA366.SMARTDMA_Boot (*C function*), 912

drivers_MCX_MCXA_MCXA366.SMARTDMA_Boot1 (*C function*), 912
drivers_MCX_MCXA_MCXA366.smartdma_callback_t (*C type*), 911
drivers_MCX_MCXA_MCXA366.SMARTDMA_CAMERA_FIRMWARE_SIZE (*C macro*), 915
drivers_MCX_MCXA_MCXA366.SMARTDMA_CAMERA_MEM_ADDR (*C macro*), 915
drivers_MCX_MCXA_MCXA366.smartdma_camera_param_t (*C type*), 914
drivers_MCX_MCXA_MCXA366.SMARTDMA_Deinit (*C function*), 913
drivers_MCX_MCXA_MCXA366.SMARTDMA_DISPLAY_FIRMWARE_SIZE (*C macro*), 915
drivers_MCX_MCXA_MCXA366.SMARTDMA_DISPLAY_MEM_ADDR (*C macro*), 915
drivers_MCX_MCXA_MCXA366.smartdma_flexio_mculcd_param_t (*C type*), 914
drivers_MCX_MCXA_MCXA366.SMARTDMA_HandleIRQ (*C function*), 913
drivers_MCX_MCXA_MCXA366.SMARTDMA_Init (*C function*), 911
drivers_MCX_MCXA_MCXA366.SMARTDMA_InitWithoutFirmware (*C function*), 912
drivers_MCX_MCXA_MCXA366.SMARTDMA_InstallCallback (*C function*), 912
drivers_MCX_MCXA_MCXA366.SMARTDMA_InstallFirmware (*C function*), 912
drivers_MCX_MCXA_MCXA366.smartdma_keyscan_4x4_param_t (*C type*), 914
drivers_MCX_MCXA_MCXA366.SMARTDMA_KEYSCAN_FIRMWARE_SIZE (*C macro*), 915
drivers_MCX_MCXA_MCXA366.SMARTDMA_KEYSCAN_MEM_ADDR (*C macro*), 915
drivers_MCX_MCXA_MCXA366.smartdma_param_t (*C union*), 916
drivers_MCX_MCXA_MCXA366.SMARTDMA_Reset (*C function*), 913
drivers_MCX_MCXA_MCXA366.SMARTDMA_SetExternalFlag (*C function*), 913
drivers_MCX_MCXA_MCXA366.smartdma_stack (*C var*), 915, 916
drivers_MCX_MCXA_MCXA366.spc_active_mode_core_ldo_option_t (*C type*), 818
drivers_MCX_MCXA_MCXA366.spc_active_mode_dcdc_option_t (*C type*), 818
drivers_MCX_MCXA_MCXA366.spc_active_mode_regulators_config_t (*C type*), 818
drivers_MCX_MCXA_MCXA366.spc_active_mode_sys_ldo_option_t (*C type*), 818
drivers_MCX_MCXA_MCXA366.spc_bandgap_mode_t (*C type*), 817
drivers_MCX_MCXA_MCXA366.SPC_CheckDCDCBurstAck (*C function*), 806
drivers_MCX_MCXA_MCXA366.SPC_CheckLowPowerReqest (*C function*), 783
drivers_MCX_MCXA_MCXA366.SPC_CheckPowerDomainLowPowerRequest (*C function*), 784
drivers_MCX_MCXA_MCXA366.SPC_CheckSwitchState (*C function*), 783
drivers_MCX_MCXA_MCXA366.SPC_ClearDCDCBurstAckFlag (*C function*), 806
drivers_MCX_MCXA_MCXA366.SPC_ClearLowPowerRequest (*C function*), 783
drivers_MCX_MCXA_MCXA366.SPC_ClearPeriphIOIsolationFlag (*C function*), 782
drivers_MCX_MCXA_MCXA366.SPC_ClearPowerDomainLowPowerRequestFlag (*C function*), 784
drivers_MCX_MCXA_MCXA366.SPC_ClearVoltageDetectStatusFlag (*C function*), 792
drivers_MCX_MCXA_MCXA366.spc_core_ldo_drive_strength_t (*C type*), 817
drivers_MCX_MCXA_MCXA366.spc_core_ldo_voltage_level_t (*C type*), 817
drivers_MCX_MCXA_MCXA366.spc_core_voltage_detect_config_t (*C type*), 818
drivers_MCX_MCXA_MCXA366.spc_dcdc_burst_config_t (*C type*), 818
drivers_MCX_MCXA_MCXA366.spc_dcdc_drive_strength_t (*C type*), 817
drivers_MCX_MCXA_MCXA366.spc_dcdc_voltage_level_t (*C type*), 817
drivers_MCX_MCXA_MCXA366.SPC_DisableActiveModeAnalogModules (*C function*), 788
drivers_MCX_MCXA_MCXA366.SPC_DisableLowPowerModeAnalogModules (*C function*), 791
drivers_MCX_MCXA_MCXA366.SPC_EnableActiveModeAnalogModules (*C function*), 788
drivers_MCX_MCXA_MCXA366.SPC_EnableActiveModeCMPBandgapBuffer (*C function*), 786
drivers_MCX_MCXA_MCXA366.SPC_EnableActiveModeCoreHighVoltageDetect (*C function*), 793
drivers_MCX_MCXA_MCXA366.SPC_EnableActiveModeCoreLowVoltageDetect (*C function*), 792
drivers_MCX_MCXA_MCXA366.SPC_EnableActiveModeIOHighVoltageDetect (*C function*), 797
drivers_MCX_MCXA_MCXA366.SPC_EnableActiveModeIOLowVoltageDetect (*C function*), 797
drivers_MCX_MCXA_MCXA366.SPC_EnableActiveModeSystemHighVoltageDetect (*C function*), 795
drivers_MCX_MCXA_MCXA366.SPC_EnableActiveModeSystemLowVoltageDetect (*C function*), 795
drivers_MCX_MCXA_MCXA366.SPC_EnableCoreLDORegulator (*C function*), 798
drivers_MCX_MCXA_MCXA366.SPC_EnableDCDCBleedResistor (*C function*), 806
drivers_MCX_MCXA_MCXA366.SPC_EnableDCDCRegulator (*C function*), 806
drivers_MCX_MCXA_MCXA366.SPC_EnableIntegratedPowerSwitchAutomatically (*C function*), 785
drivers_MCX_MCXA_MCXA366.SPC_EnableIntegratedPowerSwitchManually (*C function*), 785

drivers_MCX_MCXA_MCXA366.SPC_EnableLowPowerModeAnalogModules (*C function*), 791
drivers_MCX_MCXA_MCXA366.SPC_EnableLowPowerModeCMPBandgapBuffer (*C function*), 790
drivers_MCX_MCXA_MCXA366.SPC_EnableLowPowerModeCMPBandgapBufferMode (*C function*), 789
drivers_MCX_MCXA_MCXA366.SPC_EnableLowPowerModeCoreHighVoltageDetect (*C function*), 793
drivers_MCX_MCXA_MCXA366.SPC_EnableLowPowerModeCoreLowVoltageDetect (*C function*), 793
drivers_MCX_MCXA_MCXA366.SPC_EnableLowPowerModeCoreVDDInternalVoltageScaling (*C function*), 790
drivers_MCX_MCXA_MCXA366.SPC_EnableLowPowerModeIOHighVoltageDetect (*C function*), 797
drivers_MCX_MCXA_MCXA366.SPC_EnableLowPowerModeIOLowVoltageDetect (*C function*), 798
drivers_MCX_MCXA_MCXA366.SPC_EnableLowPowerModeLowPowerIREF (*C function*), 788
drivers_MCX_MCXA_MCXA366.SPC_EnableLowPowerModeSystemHighVoltageDetect (*C function*), 795
drivers_MCX_MCXA_MCXA366.SPC_EnableLowPowerModeSystemLowVoltageDetect (*C function*), 796
drivers_MCX_MCXA_MCXA366.SPC_EnableSRAMLdo (*C function*), 784
drivers_MCX_MCXA_MCXA366.SPC_EnableSRAMLdOLowPowerModeIREF (*C function*), 789
drivers_MCX_MCXA_MCXA366.SPC_EnableSystemLDORegulator (*C function*), 802
drivers_MCX_MCXA_MCXA366.SPC_EnableSystemLDOSinkFeature (*C function*), 802
drivers_MCX_MCXA_MCXA366.SPC_EVD_CFG_REG_EVDISO (*C macro*), 819
drivers_MCX_MCXA_MCXA366.SPC_EVD_CFG_REG_EVDISO_SHIFT (*C macro*), 819
drivers_MCX_MCXA_MCXA366.SPC_EVD_CFG_REG_EVDLPISO (*C macro*), 819
drivers_MCX_MCXA_MCXA366.SPC_EVD_CFG_REG_EVDLPISO_SHIFT (*C macro*), 819
drivers_MCX_MCXA_MCXA366.SPC_EVD_CFG_REG_EVDSTAT (*C macro*), 819
drivers_MCX_MCXA_MCXA366.SPC_EVD_CFG_REG_EVDSTAT_SHIFT (*C macro*), 819
drivers_MCX_MCXA_MCXA366.SPC_GetActiveModeBandgapMode (*C function*), 786
drivers_MCX_MCXA_MCXA366.SPC_GetActiveModeCoreLDODriveStrength (*C function*), 800
drivers_MCX_MCXA_MCXA366.SPC_GetActiveModeCoreLDOVDDVoltageLevel (*C function*), 800
drivers_MCX_MCXA_MCXA366.SPC_GetActiveModeDCDCRegulatorDriveStrength (*C function*), 808
drivers_MCX_MCXA_MCXA366.SPC_GetActiveModeDCDCRegulatorVoltageLevel (*C function*), 807
drivers_MCX_MCXA_MCXA366.SPC_GetActiveModeEnabledAnalogModules (*C function*), 788
drivers_MCX_MCXA_MCXA366.SPC_GetActiveModeSystemLDORegulatorDriveStrength (*C function*), 804
drivers_MCX_MCXA_MCXA366.SPC_GetActiveModeSystemLDORegulatorVoltageLevel (*C function*), 804
drivers_MCX_MCXA_MCXA366.SPC_GetActiveModeVoltageDetectStatus (*C function*), 786
drivers_MCX_MCXA_MCXA366.SPC_GetBusyStatusFlag (*C function*), 782
drivers_MCX_MCXA_MCXA366.SPC_GetExternalDomainsStatus (*C function*), 798
drivers_MCX_MCXA_MCXA366.SPC_GetLowPowerCoreLDOVDDDriveStrength (*C function*), 802
drivers_MCX_MCXA_MCXA366.SPC_GetLowPowerCoreLDOVDDVoltageLevel (*C function*), 802
drivers_MCX_MCXA_MCXA366.SPC_GetLowPowerModeBandgapMode (*C function*), 788
drivers_MCX_MCXA_MCXA366.SPC_GetLowPowerModeDCDCRegulatorDriveStrength (*C function*), 809
drivers_MCX_MCXA_MCXA366.SPC_GetLowPowerModeDCDCRegulatorVoltageLevel (*C function*), 809
drivers_MCX_MCXA_MCXA366.SPC_GetLowPowerModeEnabledAnalogModules (*C function*), 791
drivers_MCX_MCXA_MCXA366.SPC_GetLowPowerModeSystemLDORegulatorDriveStrength (*C function*), 805
drivers_MCX_MCXA_MCXA366.SPC_GetLowPowerModeVoltageDetectStatus (*C function*), 788
drivers_MCX_MCXA_MCXA366.SPC_GetPeriphIOIsolationStatus (*C function*), 782
drivers_MCX_MCXA_MCXA366.SPC_GetPowerDomainLowPowerMode (*C function*), 783
drivers_MCX_MCXA_MCXA366.SPC_GetRequestedLowPowerMode (*C function*), 783
drivers_MCX_MCXA_MCXA366.SPC_GetVoltageDetectStatusFlag (*C function*), 792
drivers_MCX_MCXA_MCXA366.spc_io_voltage_detect_config_t (*C type*), 818

drivers_MCX_MCXA_MCXA366.SPC_LockCoreVoltageDetectResetSetting (*C function*), 792
drivers_MCX_MCXA_MCXA366.SPC_LockIOVoltageDetectResetSetting (*C function*), 797
drivers_MCX_MCXA_MCXA366.SPC_LockSystemVoltageDetectResetSetting (*C function*), 794
drivers_MCX_MCXA_MCXA366.spc_low_voltage_level_select_t (*C type*), 817
drivers_MCX_MCXA_MCXA366.spc_lowpower_mode_core_ldo_option_t (*C type*), 818
drivers_MCX_MCXA_MCXA366.spc_lowpower_mode_dcdc_option_t (*C type*), 818
drivers_MCX_MCXA_MCXA366.spc_lowpower_mode_regulators_config_t (*C type*), 819
drivers_MCX_MCXA_MCXA366.spc_lowpower_mode_sys_ldo_option_t (*C type*), 818
drivers_MCX_MCXA_MCXA366.spc_lowpower_request_config_t (*C type*), 818
drivers_MCX_MCXA_MCXA366.spc_lowpower_request_output_override_t (*C type*), 817
drivers_MCX_MCXA_MCXA366.spc_lowpower_request_pin_polarity_t (*C type*), 817
drivers_MCX_MCXA_MCXA366.spc_power_domain_id_t (*C type*), 817
drivers_MCX_MCXA_MCXA366.spc_power_domain_low_power_mode_t (*C type*), 817
drivers_MCX_MCXA_MCXA366.SPC_PullDownCoreLDORegulator (*C function*), 799
drivers_MCX_MCXA_MCXA366.SPC_RetainSRAMArray (*C function*), 784
drivers_MCX_MCXA_MCXA366.SPC_SetActiveModeBandgapModeConfig (*C function*), 786
drivers_MCX_MCXA_MCXA366.SPC_SetActiveModeCoreLDORegulatorConfig (*C function*), 799
drivers_MCX_MCXA_MCXA366.SPC_SetActiveModeCoreLDORegulatorDriveStrength (*C function*), 800
drivers_MCX_MCXA_MCXA366.SPC_SetActiveModeCoreLDORegulatorVoltageLevel (*C function*), 799
drivers_MCX_MCXA_MCXA366.SPC_SetActiveModeDCDCRegulatorConfig (*C function*), 807
drivers_MCX_MCXA_MCXA366.SPC_SetActiveModeDCDCRegulatorDriveStrength (*C function*), 807
drivers_MCX_MCXA_MCXA366.SPC_SetActiveModeDCDCRegulatorVoltageLevel (*C function*), 807
drivers_MCX_MCXA_MCXA366.SPC_SetActiveModeRegulatorsConfig (*C function*), 787
drivers_MCX_MCXA_MCXA366.SPC_SetActiveModeSystemLDORegulatorConfig (*C function*), 803
drivers_MCX_MCXA_MCXA366.SPC_SetActiveModeSystemLDORegulatorDriveStrength (*C function*), 804
drivers_MCX_MCXA_MCXA366.SPC_SetActiveModeSystemLDORegulatorVoltageLevel (*C function*), 803
drivers_MCX_MCXA_MCXA366.SPC_SetActiveModeVoltageTrimDelay (*C function*), 787
drivers_MCX_MCXA_MCXA366.SPC_SetCoreVoltageDetectConfig (*C function*), 792
drivers_MCX_MCXA_MCXA366.SPC_SetDCDCBurstConfig (*C function*), 806
drivers_MCX_MCXA_MCXA366.SPC_SetDCDCRefreshCount (*C function*), 806
drivers_MCX_MCXA_MCXA366.SPC_SetExternalVoltageDomainsConfig (*C function*), 798
drivers_MCX_MCXA_MCXA366.SPC_SetIOVDDLowVoltageLevel (*C function*), 796
drivers_MCX_MCXA_MCXA366.SPC_SetIOVoltageDetectConfig (*C function*), 796
drivers_MCX_MCXA_MCXA366.SPC_SetLowPowerModeBandgapmodeConfig (*C function*), 789
drivers_MCX_MCXA_MCXA366.SPC_SetLowPowerModeCoreLDORegulatorConfig (*C function*), 801
drivers_MCX_MCXA_MCXA366.SPC_SetLowPowerModeCoreLDORegulatorDriveStrength (*C function*), 802
drivers_MCX_MCXA_MCXA366.SPC_SetLowPowerModeCoreLDORegulatorVoltageLevel (*C function*), 801
drivers_MCX_MCXA_MCXA366.SPC_SetLowPowerModeDCDCRegulatorConfig (*C function*), 808
drivers_MCX_MCXA_MCXA366.SPC_SetLowPowerModeDCDCRegulatorDriveStrength (*C function*), 808
drivers_MCX_MCXA_MCXA366.SPC_SetLowPowerModeDCDCRegulatorVoltageLevel (*C function*), 809
drivers_MCX_MCXA_MCXA366.SPC_SetLowPowerModeRegulatorsConfig (*C function*), 790
drivers_MCX_MCXA_MCXA366.SPC_SetLowPowerModeSystemLDORegulatorConfig (*C function*), 805
drivers_MCX_MCXA_MCXA366.SPC_SetLowPowerModeSystemLDORegulatorDriveStrength (*C function*), 805
drivers_MCX_MCXA_MCXA366.SPC_SetLowPowerRequestConfig (*C function*), 785
drivers_MCX_MCXA_MCXA366.SPC_SetLowPowerWakeUpDelay (*C function*), 790

drivers_MCX_MCXA_MCXA366.SPC_SetSRAMOperateVoltage (*C function*), 785
drivers_MCX_MCXA_MCXA366.SPC_SetSystemVDDLowVoltageLevel (*C function*), 794
drivers_MCX_MCXA_MCXA366.SPC_SetSystemVoltageDetectConfig (*C function*), 794
drivers_MCX_MCXA_MCXA366.spc_sram_operate_voltage_t (*C type*), 818
drivers_MCX_MCXA_MCXA366.spc_sram_voltage_config_t (*C type*), 818
drivers_MCX_MCXA_MCXA366.spc_sys_ldo_drive_strength_t (*C type*), 817
drivers_MCX_MCXA_MCXA366.spc_sys_ldo_voltage_level_t (*C type*), 817
drivers_MCX_MCXA_MCXA366.spc_system_voltage_detect_config_t (*C type*), 818
drivers_MCX_MCXA_MCXA366.SPC_TriggerDCDCBurstRequest (*C function*), 806
drivers_MCX_MCXA_MCXA366.SPC_TrimSRAMLdoRefVoltage (*C function*), 784
drivers_MCX_MCXA_MCXA366.SPC_UnlockCoreVoltageDetectResetSetting (*C function*), 792
drivers_MCX_MCXA_MCXA366.SPC_UnlockIOVoltageDetectResetSetting (*C function*), 797
drivers_MCX_MCXA_MCXA366.SPC_UnlockSystemVoltageDetectResetSetting (*C function*), 795
drivers_MCX_MCXA_MCXA366.SPC_UnRetainSRAMArray (*C function*), 784
drivers_MCX_MCXA_MCXA366.spc_voltage_detect_option_t (*C type*), 818
drivers_MCX_MCXA_MCXA366.SPI_RETRY_TIMES (*C macro*), 454, 720
drivers_MCX_MCXA_MCXA366.status_t (*C type*), 627
drivers_MCX_MCXA_MCXA366.SUPPRESS_FALL_THROUGH_WARNING (*C macro*), 630
drivers_MCX_MCXA_MCXA366.T_FORMAT_ABM_BYTE (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_ABS_BYTE (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_ADF_MASK_ADDRESS (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_ALL_INFO_BYTE (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_ALMC_MASK_BATTERY_ALARM (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_ALMC_MASK_BATTERY_ERROR (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_ALMC_MASK_COUNTER_OVERFLOW (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_ALMC_MASK_COUNTING_ERROR (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_ALMC_MASK_FULL_ABSOLUTE_STATUS (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_ALMC_MASK_MULTITURN_ERROR (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_ALMC_MASK_OVER_SPEED (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_ALMC_MASK_OVERHEAT (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_BITS_PER_FRAME_DATA (*C macro*), 468
drivers_MCX_MCXA_MCXA366.T_FORMAT_BITS_PER_FRAME_WHOLE (*C macro*), 468
drivers_MCX_MCXA_MCXA366.T_FORMAT_CF (*C macro*), 466
drivers_MCX_MCXA_MCXA366.T_FORMAT_CF_DATA_ID_CODE (*C macro*), 466
drivers_MCX_MCXA_MCXA366.T_FORMAT_CF_EEPROM_READOUT (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_CF_EEPROM_WRITE (*C macro*), 466
drivers_MCX_MCXA_MCXA366.T_FORMAT_CF_GET_ABM (*C macro*), 466
drivers_MCX_MCXA_MCXA366.T_FORMAT_CF_GET_ABS (*C macro*), 466
drivers_MCX_MCXA_MCXA366.T_FORMAT_CF_GET_ALL (*C macro*), 466
drivers_MCX_MCXA_MCXA366.T_FORMAT_CF_GET_ENCID (*C macro*), 466
drivers_MCX_MCXA_MCXA366.T_FORMAT_CF_ID_PARITY (*C macro*), 466
drivers_MCX_MCXA_MCXA366.T_FORMAT_CF_MASK_DATA_ID_CODE (*C macro*), 466
drivers_MCX_MCXA_MCXA366.T_FORMAT_CF_MASK_ID_PARITY (*C macro*), 466
drivers_MCX_MCXA_MCXA366.T_FORMAT_CF_MASK_SINK_CODE (*C macro*), 466
drivers_MCX_MCXA_MCXA366.T_FORMAT_CF_RESET_ABM_ERROR (*C macro*), 466
drivers_MCX_MCXA_MCXA366.T_FORMAT_CF_RESET_ABS (*C macro*), 466
drivers_MCX_MCXA_MCXA366.T_FORMAT_CF_RESET_ALL_ERROR (*C macro*), 466
drivers_MCX_MCXA_MCXA366.T_FORMAT_CRC_POLYNOMIAL (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_DATA_ID (*C macro*), 466
drivers_MCX_MCXA_MCXA366.T_FORMAT_EEPROM_BYTE (*C macro*), 468
drivers_MCX_MCXA_MCXA366.T_FORMAT_ENCODER_ID_BYTE (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_ENCODER_MAX_NUM (*C macro*), 468

drivers_MCX_MCXA_MCXA366.T_FORMAT_OVER_HEAT_NOT_CAUSE (*C macro*), 468
drivers_MCX_MCXA_MCXA366.T_FORMAT_OVER_HEAT_TEMPERATURE (*C macro*), 468
drivers_MCX_MCXA_MCXA366.T_FORMAT_RETRY_TIMES (*C macro*), 468
drivers_MCX_MCXA_MCXA366.T_FORMAT_SF_GET_COMMUNICATION_ALARM (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_SF_GET_ENCODER_ERROR (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_SF_MASK_BUSY_STATUS (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_SF_MASK_COMMUNICATION_ALARM (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_SF_MASK_ENCODER_ERROR (*C macro*), 467
drivers_MCX_MCXA_MCXA366.T_FORMAT_SINK_CODE_CF (*C macro*), 466
drivers_MCX_MCXA_MCXA366.T_FORMAT_TIMER_COMPARE_VALUE (*C macro*), 468
drivers_MCX_MCXA_MCXA366.T_FORMAT_TIMER_DR_INDEX (*C macro*), 468
drivers_MCX_MCXA_MCXA366.T_FORMAT_TIMER_RX_INDEX (*C macro*), 468
drivers_MCX_MCXA_MCXA366.T_FORMAT_TIMER_TX_INDEX (*C macro*), 468
drivers_MCX_MCXA_MCXA366.tdet_active_tamper_clock_t (*C type*), 926
drivers_MCX_MCXA_MCXA366.tdet_active_tamper_config_t (*C type*), 928
drivers_MCX_MCXA_MCXA366.tdet_active_tamper_register_t (*C type*), 927
drivers_MCX_MCXA_MCXA366.TDET_ClearStatusFlags (*C function*), 918
drivers_MCX_MCXA_MCXA366.tdet_config_t (*C type*), 927
drivers_MCX_MCXA_MCXA366.TDET_Deinit (*C function*), 916
drivers_MCX_MCXA_MCXA366.TDET_DisableInterrupts (*C function*), 919
drivers_MCX_MCXA_MCXA366.TDET_DisableTampers (*C function*), 919
drivers_MCX_MCXA_MCXA366.TDET_EnableInterrupts (*C function*), 919
drivers_MCX_MCXA_MCXA366.TDET_EnableTampers (*C function*), 919
drivers_MCX_MCXA_MCXA366.tdet_external_tamper_pin_t (*C type*), 927
drivers_MCX_MCXA_MCXA366.TDET_ForceTamper (*C function*), 919
drivers_MCX_MCXA_MCXA366.TDET_GetDefaultConfig (*C function*), 916
drivers_MCX_MCXA_MCXA366.TDET_GetStatusFlags (*C function*), 918
drivers_MCX_MCXA_MCXA366.TDET_GetTamperTimeSeconds (*C function*), 920
drivers_MCX_MCXA_MCXA366.tdet_glitch_filter_expected_t (*C type*), 927
drivers_MCX_MCXA_MCXA366.tdet_glitch_filter_prescaler_t (*C type*), 927
drivers_MCX_MCXA_MCXA366.tdet_glitch_filter_pull_t (*C type*), 927
drivers_MCX_MCXA_MCXA366.tdet_glitch_filter_sample_freq_t (*C type*), 927
drivers_MCX_MCXA_MCXA366.tdet_glitch_filter_sample_width_t (*C type*), 927
drivers_MCX_MCXA_MCXA366.TDET_Init (*C function*), 916
drivers_MCX_MCXA_MCXA366.tdet_interrupt_t (*C type*), 928
drivers_MCX_MCXA_MCXA366.TDET_LockRegisters (*C function*), 920
drivers_MCX_MCXA_MCXA366.tdet_pin_config_t (*C type*), 927
drivers_MCX_MCXA_MCXA366.tdet_pin_direction_t (*C type*), 927
drivers_MCX_MCXA_MCXA366.tdet_pin_polarity_t (*C type*), 927
drivers_MCX_MCXA_MCXA366.TDET_PinGetDefaultConfig (*C function*), 917
drivers_MCX_MCXA_MCXA366.TDET_PinSetConfig (*C function*), 918
drivers_MCX_MCXA_MCXA366.tdet_register_t (*C type*), 928
drivers_MCX_MCXA_MCXA366.TDET_SetConfig (*C function*), 917
drivers_MCX_MCXA_MCXA366.TDET_SoftwareReset (*C function*), 917
drivers_MCX_MCXA_MCXA366.tdet_status_flag_t (*C type*), 928
drivers_MCX_MCXA_MCXA366.tdet_tamper_t (*C type*), 928
drivers_MCX_MCXA_MCXA366.tdet_update_mode_t (*C type*), 926
drivers_MCX_MCXA_MCXA366.timerDiv (*C var*), 367, 468
drivers_MCX_MCXA_MCXA366.timerIndex (*C var*), 367, 469
drivers_MCX_MCXA_MCXA366.trdc_controller_t (*C type*), 948
drivers_MCX_MCXA_MCXA366.TRDC_Deinit (*C function*), 930
drivers_MCX_MCXA_MCXA366.trdc_did_sel_t (*C type*), 948
drivers_MCX_MCXA_MCXA366.TRDC_DOMAIN_ASSIGNMENT_BASE (*C macro*), 956
drivers_MCX_MCXA_MCXA366.TRDC_DOMAIN_ERROR_BASE (*C macro*), 956
drivers_MCX_MCXA_MCXA366.trdc_domain_error_t (*C type*), 949
drivers_MCX_MCXA_MCXA366.TRDC_DomainAssignment_Type (*C type*), 956

drivers_MCX_MCXA_MCXA366.TRDC_DomainError_Type (*C type*), 956
drivers_MCX_MCXA_MCXA366.TRDC_EnableFlashLogicalWindow (*C function*), 934
drivers_MCX_MCXA_MCXA366.trdc_error_attr_t (*C type*), 949
drivers_MCX_MCXA_MCXA366.trdc_error_state_t (*C type*), 948
drivers_MCX_MCXA_MCXA366.trdc_error_type_t (*C type*), 949
drivers_MCX_MCXA_MCXA366.TRDC_FLW_BASE (*C macro*), 956
drivers_MCX_MCXA_MCXA366.trdc_flw_config_t (*C type*), 948
drivers_MCX_MCXA_MCXA366.TRDC_FLW_Type (*C type*), 956
drivers_MCX_MCXA_MCXA366.TRDC_GENERAL_BASE (*C macro*), 956
drivers_MCX_MCXA_MCXA366.TRDC_General_Type (*C type*), 956
drivers_MCX_MCXA_MCXA366.TRDC_GetActiveMasterPidMap (*C function*), 933
drivers_MCX_MCXA_MCXA366.TRDC_GetAndClearFirstDomainError (*C function*), 935
drivers_MCX_MCXA_MCXA366.TRDC_GetAndClearFirstSpecificDomainError (*C function*), 935
drivers_MCX_MCXA_MCXA366.TRDC_GetCurrentMasterDomainId (*C function*), 930
drivers_MCX_MCXA_MCXA366.TRDC_GetDefaultFlashLogicalWindowConfig (*C function*), 934
drivers_MCX_MCXA_MCXA366.TRDC_GetDefaultIDAUConfig (*C function*), 933
drivers_MCX_MCXA_MCXA366.TRDC_GetDefaultNonProcessorDomainAssignment (*C function*), 931
drivers_MCX_MCXA_MCXA366.TRDC_GetDefaultProcessorDomainAssignment (*C function*), 931
drivers_MCX_MCXA_MCXA366.TRDC_GetFlashLogicalWindowPbase (*C function*), 934
drivers_MCX_MCXA_MCXA366.TRDC_GetHardwareConfig (*C function*), 930
drivers_MCX_MCXA_MCXA366.TRDC_GetMbcHardwareConfig (*C function*), 937
drivers_MCX_MCXA_MCXA366.TRDC_GetMrcRegionNumber (*C function*), 935
drivers_MCX_MCXA_MCXA366.TRDC_GetSetFlashLogicalWindowSize (*C function*), 934
drivers_MCX_MCXA_MCXA366.trdc_hardware_config_t (*C type*), 948
drivers_MCX_MCXA_MCXA366.trdc_idau_config_t (*C type*), 948
drivers_MCX_MCXA_MCXA366.TRDC_Init (*C function*), 930
drivers_MCX_MCXA_MCXA366.TRDC_LockFlashLogicalWindow (*C function*), 934
drivers_MCX_MCXA_MCXA366.TRDC_LockMasterDomainAssignment (*C function*), 931
drivers_MCX_MCXA_MCXA366.TRDC_MBC_BASE (*C macro*), 956
drivers_MCX_MCXA_MCXA366.trdc_mbc_memory_block_config_t (*C type*), 949
drivers_MCX_MCXA_MCXA366.trdc_mbc_nse_update_config_t (*C type*), 949
drivers_MCX_MCXA_MCXA366.TRDC_MBC_Type (*C type*), 956
drivers_MCX_MCXA_MCXA366.TRDC_MbcNseClearAll (*C function*), 938
drivers_MCX_MCXA_MCXA366.TRDC_MbcSetMemoryAccessConfig (*C function*), 938
drivers_MCX_MCXA_MCXA366.TRDC_MbcSetMemoryBlockConfig (*C function*), 938
drivers_MCX_MCXA_MCXA366.TRDC_MbcSetNseUpdateConfig (*C function*), 937
drivers_MCX_MCXA_MCXA366.TRDC_MbcWordNseClear (*C function*), 938
drivers_MCX_MCXA_MCXA366.TRDC_MbcWordNseSet (*C function*), 937
drivers_MCX_MCXA_MCXA366.trdc_memory_access_control_config_t (*C type*), 949
drivers_MCX_MCXA_MCXA366.TRDC_MRC_BASE (*C macro*), 956
drivers_MCX_MCXA_MCXA366.trdc_mrc_region_descriptor_config_t (*C type*), 949
drivers_MCX_MCXA_MCXA366.TRDC_MRC_Type (*C type*), 956
drivers_MCX_MCXA_MCXA366.TRDC_MrcDomainNseClear (*C function*), 937
drivers_MCX_MCXA_MCXA366.TRDC_MrcEnableDomainNseUpdate (*C function*), 936
drivers_MCX_MCXA_MCXA366.TRDC_MrcRegionNseClear (*C function*), 936
drivers_MCX_MCXA_MCXA366.TRDC_MrcRegionNseSet (*C function*), 936
drivers_MCX_MCXA_MCXA366.TRDC_MrcSetMemoryAccessConfig (*C function*), 936
drivers_MCX_MCXA_MCXA366.TRDC_MrcSetRegionDescriptorConfig (*C function*), 937
drivers_MCX_MCXA_MCXA366.trdc_non_processor_domain_assignment_t (*C type*), 948
drivers_MCX_MCXA_MCXA366.trdc_pid_config_t (*C type*), 948
drivers_MCX_MCXA_MCXA366.trdc_pid_domain_hit_config_t (*C type*), 948
drivers_MCX_MCXA_MCXA366.trdc_pid_lock_t (*C type*), 948
drivers_MCX_MCXA_MCXA366.trdc_privilege_attr_t (*C type*), 948
drivers_MCX_MCXA_MCXA366.trdc_processor_domain_assignment_t (*C type*), 948
drivers_MCX_MCXA_MCXA366.trdc_secure_attr_t (*C type*), 948
drivers_MCX_MCXA_MCXA366.TRDC_SetDacGlobalValid (*C function*), 930
drivers_MCX_MCXA_MCXA366.TRDC_SetFlashLogicalWindow (*C function*), 934

drivers_MCX_MCXA_MCXA366.TRDC_SetIDAU (*C function*), 933
drivers_MCX_MCXA_MCXA366.TRDC_SetMasterDomainAssignmentValid (*C function*), 931
drivers_MCX_MCXA_MCXA366.TRDC_SetMbcGlobalValid (*C function*), 937
drivers_MCX_MCXA_MCXA366.TRDC_SetMrcGlobalValid (*C function*), 935
drivers_MCX_MCXA_MCXA366.TRDC_SetNonProcessorDomainAssignment (*C function*), 932
drivers_MCX_MCXA_MCXA366.TRDC_SetPid (*C function*), 933
drivers_MCX_MCXA_MCXA366.TRDC_SetProcessorDomainAssignment (*C function*), 932
drivers_MCX_MCXA_MCXA366.trdc_slave_memory_hardware_config_t (*C type*), 948
drivers_MCX_MCXA_MCXA366.triggerIn (*C var*), 367, 469
drivers_MCX_MCXA_MCXA366.trng_clock_mode_t (*C type*), 975
drivers_MCX_MCXA_MCXA366.trng_config_t (*C type*), 975
drivers_MCX_MCXA_MCXA366.TRNG_Deinit (*C function*), 975
drivers_MCX_MCXA_MCXA366.TRNG_GetDefaultConfig (*C function*), 975
drivers_MCX_MCXA_MCXA366.TRNG_GetRandomData (*C function*), 976
drivers_MCX_MCXA_MCXA366.TRNG_Init (*C function*), 975
drivers_MCX_MCXA_MCXA366.trng_oscillator_mode_t (*C enum*), 974
drivers_MCX_MCXA_MCXA366.trng_oscillator_mode_t (*C type*), 975
drivers_MCX_MCXA_MCXA366.trng_oscillator_mode_t.kTRNG_DualOscillatorMode (*C enumerator*), 974
drivers_MCX_MCXA_MCXA366.trng_oscillator_mode_t.kTRNG_SingleOscillatorModeOsc1 (*C enumerator*), 974
drivers_MCX_MCXA_MCXA366.trng_oscillator_mode_t.kTRNG_SingleOscillatorModeOsc2 (*C enumerator*), 975
drivers_MCX_MCXA_MCXA366.trng_ring_osc_div_t (*C type*), 975
drivers_MCX_MCXA_MCXA366.trng_sample_mode_t (*C type*), 975
drivers_MCX_MCXA_MCXA366.trng_statistical_check_limit_t (*C type*), 975
drivers_MCX_MCXA_MCXA366.txData (*C var*), 368, 469
drivers_MCX_MCXA_MCXA366.txDataSize (*C var*), 368, 469
drivers_MCX_MCXA_MCXA366.txDataSizeAll (*C var*), 368, 470
drivers_MCX_MCXA_MCXA366.TxDR_Offset (*C var*), 367, 468
drivers_MCX_MCXA_MCXA366.TxPinIndex (*C var*), 367, 468
drivers_MCX_MCXA_MCXA366.txState (*C var*), 368, 470
drivers_MCX_MCXA_MCXA366.UART_RETRY_TIMES (*C macro*), 480, 757
drivers_MCX_MCXA_MCXA366.UINT16_MAX (*C macro*), 615
drivers_MCX_MCXA_MCXA366.UINT32_MAX (*C macro*), 615
drivers_MCX_MCXA_MCXA366.UINT64_H (*C macro*), 615
drivers_MCX_MCXA_MCXA366.UINT64_L (*C macro*), 615
drivers_MCX_MCXA_MCXA366.UINTPTR_SIZE (*C macro*), 615
drivers_MCX_MCXA_MCXA366.USEC_TO_COUNT (*C macro*), 617
drivers_MCX_MCXA_MCXA366.userData (*C var*), 368, 470
drivers_MCX_MCXA_MCXA366.userMode (*C var*), 367, 469
drivers_MCX_MCXA_MCXA366.utick_callback_t (*C type*), 979
drivers_MCX_MCXA_MCXA366.UTICK_ClearStatusFlags (*C function*), 978
drivers_MCX_MCXA_MCXA366.UTICK_Deinit (*C function*), 978
drivers_MCX_MCXA_MCXA366.UTICK_GetStatusFlags (*C function*), 978
drivers_MCX_MCXA_MCXA366.UTICK_HandleIRQ (*C function*), 979
drivers_MCX_MCXA_MCXA366.UTICK_Init (*C function*), 978
drivers_MCX_MCXA_MCXA366.utick_mode_t (*C type*), 979
drivers_MCX_MCXA_MCXA366.UTICK_SetTick (*C function*), 978
drivers_MCX_MCXA_MCXA366.VBAT0_DriverIRQHandler (*C function*), 928
drivers_MCX_MCXA_MCXA366.VBAT_AdjustCrystalOsc32kAmplifierGain (*C function*), 834
drivers_MCX_MCXA_MCXA366.vbat_bandgap_refresh_period_t (*C type*), 831
drivers_MCX_MCXA_MCXA366.vbat_bandgap_timer0_timeout_period_t (*C type*), 831
drivers_MCX_MCXA_MCXA366.VBAT_BypassCrystalOsc32k (*C function*), 834
drivers_MCX_MCXA_MCXA366.VBAT_CheckBandgapEnabled (*C function*), 836
drivers_MCX_MCXA_MCXA366.VBAT_CheckClockMonitorControlLocked (*C function*), 842
drivers_MCX_MCXA_MCXA366.VBAT_CheckFRO16kEnabled (*C function*), 833
drivers_MCX_MCXA_MCXA366.VBAT_CheckFRO16kSettingsLocked (*C function*), 833

drivers_MCX_MCXA_MCXA366.VBAT_CheckOsc32kSettingsLocked (*C function*), 835
drivers_MCX_MCXA_MCXA366.VBAT_CheckRamLdoSettingsLocked (*C function*), 837
drivers_MCX_MCXA_MCXA366.VBAT_CheckSwitchControlLocked (*C function*), 840
drivers_MCX_MCXA_MCXA366.VBAT_CheckTamperControlLocked (*C function*), 843
drivers_MCX_MCXA_MCXA366.VBAT_ClearStatusFlags (*C function*), 844
drivers_MCX_MCXA_MCXA366.vbat_clock_monitor_config_t (*C type*), 832
drivers_MCX_MCXA_MCXA366.vbat_clock_monitor_divide_trim_t (*C type*), 832
drivers_MCX_MCXA_MCXA366.vbat_clock_monitor_freq_trim_t (*C type*), 832
drivers_MCX_MCXA_MCXA366.VBAT_ConfigFRO16k (*C function*), 832
drivers_MCX_MCXA_MCXA366.VBAT_DeinitMonitor (*C function*), 841
drivers_MCX_MCXA_MCXA366.VBAT_DeinitTamper (*C function*), 843
drivers_MCX_MCXA_MCXA366.VBAT_DisableInterrupts (*C function*), 844
drivers_MCX_MCXA_MCXA366.VBAT_DisableTamper (*C function*), 843
drivers_MCX_MCXA_MCXA366.VBAT_DisableWakeup (*C function*), 844
drivers_MCX_MCXA_MCXA366.VBAT_EnableBackupSRAMRegulator (*C function*), 837
drivers_MCX_MCXA_MCXA366.VBAT_EnableBandgap (*C function*), 836
drivers_MCX_MCXA_MCXA366.VBAT_EnableBandgapRefreshMode (*C function*), 836
drivers_MCX_MCXA_MCXA366.VBAT_EnableBandgapTimer (*C function*), 839
drivers_MCX_MCXA_MCXA366.VBAT_EnableClockMonitor (*C function*), 841
drivers_MCX_MCXA_MCXA366.VBAT_EnableCrystalOsc32k (*C function*), 833
drivers_MCX_MCXA_MCXA366.VBAT_EnableFRO16k (*C function*), 832
drivers_MCX_MCXA_MCXA366.VBAT_EnableInterrupts (*C function*), 844
drivers_MCX_MCXA_MCXA366.VBAT_EnableSRAMIsolation (*C function*), 838
drivers_MCX_MCXA_MCXA366.VBAT_EnableTamper (*C function*), 843
drivers_MCX_MCXA_MCXA366.VBAT_EnableWakeup (*C function*), 844
drivers_MCX_MCXA_MCXA366.vbat_fro16k_config_t (*C type*), 832
drivers_MCX_MCXA_MCXA366.VBAT_GateFRO16k (*C function*), 833
drivers_MCX_MCXA_MCXA366.VBAT_GateOsc32k (*C function*), 836
drivers_MCX_MCXA_MCXA366.VBAT_GetStatusFlags (*C function*), 844
drivers_MCX_MCXA_MCXA366.VBAT_GetTamperEnableInfo (*C function*), 843
drivers_MCX_MCXA_MCXA366.VBAT_GetVBATModuleSupply (*C function*), 840
drivers_MCX_MCXA_MCXA366.VBAT_InitClockMonitor (*C function*), 840
drivers_MCX_MCXA_MCXA366.VBAT_InitTamper (*C function*), 842
drivers_MCX_MCXA_MCXA366.vbat_internal_module_supply_t (*C type*), 832
drivers_MCX_MCXA_MCXA366.VBAT_LDORAMC_RET (*C macro*), 832
drivers_MCX_MCXA_MCXA366.VBAT_LDORAMC_RET_MASK (*C macro*), 832
drivers_MCX_MCXA_MCXA366.VBAT_LDORAMC_RET_SHIFT (*C macro*), 832
drivers_MCX_MCXA_MCXA366.VBAT_LockClockMonitorControl (*C function*), 842
drivers_MCX_MCXA_MCXA366.VBAT_LockFRO16kSettings (*C function*), 833
drivers_MCX_MCXA_MCXA366.VBAT_LockInterruptWakeupSettings (*C function*), 845
drivers_MCX_MCXA_MCXA366.VBAT_LockRamLdoSettings (*C function*), 837
drivers_MCX_MCXA_MCXA366.VBAT_LockSwitchControl (*C function*), 840
drivers_MCX_MCXA_MCXA366.VBAT_LockTamperControl (*C function*), 843
drivers_MCX_MCXA_MCXA366.VBAT_LookOsc32kSettings (*C function*), 835
drivers_MCX_MCXA_MCXA366.vbat_osc32k_load_capacitance_select_t (*C type*), 831
drivers_MCX_MCXA_MCXA366.vbat_osc32k_operate_mode_t (*C type*), 831
drivers_MCX_MCXA_MCXA366.vbat_osc32k_start_up_time_t (*C type*), 832
drivers_MCX_MCXA_MCXA366.VBAT_PowerOffSRAMsInLowPowerModes (*C function*), 838
drivers_MCX_MCXA_MCXA366.VBAT_RetainSRAMsInLowPowerModes (*C function*), 838
drivers_MCX_MCXA_MCXA366.VBAT_SetBandgapTimer0TimeoutValue (*C function*), 839
drivers_MCX_MCXA_MCXA366.VBAT_SetBandgapTimer1TimeoutValue (*C function*), 839
drivers_MCX_MCXA_MCXA366.VBAT_SetClockMonitorDivideTrim (*C function*), 841
drivers_MCX_MCXA_MCXA366.VBAT_SetClockMonitorFrequencyTrim (*C function*), 841
drivers_MCX_MCXA_MCXA366.VBAT_SetCrystalOsc32kModeAndLoadCapacitance (*C function*), 834
drivers_MCX_MCXA_MCXA366.VBAT_SetOsc32kSwitchModeCapacitorTrimValue (*C function*), 835

drivers_MCX_MCXA_MCXA366.VBAT_SetOsc32kSwitchModeComparatorTrimValue (*C function*), 835
drivers_MCX_MCXA_MCXA366.VBAT_SetOsc32kSwitchModeDelayTrimValue (*C function*), 835
drivers_MCX_MCXA_MCXA366.VBAT_SetWakeupPinDefaultState (*C function*), 845
drivers_MCX_MCXA_MCXA366.VBAT_SwitchSRAMPowerByLDOSRAM (*C function*), 837
drivers_MCX_MCXA_MCXA366.VBAT_SwitchSRAMPowerBySocSupply (*C function*), 838
drivers_MCX_MCXA_MCXA366.VBAT_SwitchVBATModuleSupplyActiveMode (*C function*), 839
drivers_MCX_MCXA_MCXA366.VBAT_SwitchVBATModuleSupplyLowPowerMode (*C function*), 840
drivers_MCX_MCXA_MCXA366.vbat_tamper_config_t (*C type*), 832
drivers_MCX_MCXA_MCXA366.VBAT_TrimCrystalOsc32kStartupTime (*C function*), 835
drivers_MCX_MCXA_MCXA366.VBAT_UngateFRO16k (*C function*), 833
drivers_MCX_MCXA_MCXA366.VBAT_UngateOsc32k (*C function*), 836
drivers_MCX_MCXA_MCXA366.VBAT_UnlockClockMonitorControl (*C function*), 842
drivers_MCX_MCXA_MCXA366.VBAT_UnlockOsc32kSettings (*C function*), 835
drivers_MCX_MCXA_MCXA366.VBAT_UnlockSwitchControl (*C function*), 840
drivers_MCX_MCXA_MCXA366.VBAT_UnlockTamperControl (*C function*), 843
drivers_MCX_MCXA_MCXA366.waketimer_callback_t (*C type*), 981
drivers_MCX_MCXA_MCXA366.WAKETIMER_ClearStatusFlags (*C function*), 980
drivers_MCX_MCXA_MCXA366.waketimer_config_t (*C type*), 981
drivers_MCX_MCXA_MCXA366.WAKETIMER_Deinit (*C function*), 979
drivers_MCX_MCXA_MCXA366.WAKETIMER_DisableInterrupts (*C function*), 980
drivers_MCX_MCXA_MCXA366.WAKETIMER_EnableInterrupts (*C function*), 980
drivers_MCX_MCXA_MCXA366.WAKETIMER_GetCurrentTimerValue (*C function*), 981
drivers_MCX_MCXA_MCXA366.WAKETIMER_GetDefaultConfig (*C function*), 980
drivers_MCX_MCXA_MCXA366.WAKETIMER_HaltTimer (*C function*), 980
drivers_MCX_MCXA_MCXA366.WAKETIMER_Init (*C function*), 979
drivers_MCX_MCXA_MCXA366.WAKETIMER_SetCallback (*C function*), 980
drivers_MCX_MCXA_MCXA366.WAKETIMER_StartTimer (*C function*), 981
drivers_MCX_MCXA_MCXA366.WUU_ClearExternalWakeupPinFlag (*C function*), 984
drivers_MCX_MCXA_MCXA366.WUU_ClearExternalWakeupPinsConfig (*C function*), 982
drivers_MCX_MCXA_MCXA366.WUU_ClearExternalWakeUpPinsFlag (*C function*), 983
drivers_MCX_MCXA_MCXA366.WUU_ClearInternalWakeUpModulesConfig (*C function*), 983
drivers_MCX_MCXA_MCXA366.WUU_ClearPinFilterFlag (*C function*), 984
drivers_MCX_MCXA_MCXA366.wuu_external_pin_edge_detection_t (*C type*), 987
drivers_MCX_MCXA_MCXA366.wuu_external_wakeup_pin_config_t (*C type*), 987
drivers_MCX_MCXA_MCXA366.wuu_external_wakeup_pin_event_t (*C type*), 987
drivers_MCX_MCXA_MCXA366.wuu_external_wakeup_pin_mode_t (*C type*), 987
drivers_MCX_MCXA_MCXA366.wuu_filter_edge_t (*C type*), 987
drivers_MCX_MCXA_MCXA366.wuu_filter_event_t (*C type*), 987
drivers_MCX_MCXA_MCXA366.wuu_filter_mode_t (*C type*), 987
drivers_MCX_MCXA_MCXA366.WUU_GetExternalWakeupPinFlag (*C function*), 984
drivers_MCX_MCXA_MCXA366.WUU_GetExternalWakeUpPinsFlag (*C function*), 982
drivers_MCX_MCXA_MCXA366.WUU_GetInternalWakeupModuleFlag (*C function*), 983
drivers_MCX_MCXA_MCXA366.WUU_GetModuleInterruptFlag (*C function*), 983
drivers_MCX_MCXA_MCXA366.WUU_GetPinFilterFlag (*C function*), 984
drivers_MCX_MCXA_MCXA366.wuu_internal_wakeup_module_event_t (*C type*), 987
drivers_MCX_MCXA_MCXA366.wuu_pin_filter_config_t (*C type*), 987
drivers_MCX_MCXA_MCXA366.WUU_SetExternalWakeUpPinsConfig (*C function*), 982
drivers_MCX_MCXA_MCXA366.WUU_SetInternalWakeUpModulesConfig (*C function*), 983
drivers_MCX_MCXA_MCXA366.WUU_SetPinFilterConfig (*C function*), 984
drivers_MCX_MCXA_MCXA366.WWDT_ClearStatusFlags (*C function*), 989
drivers_MCX_MCXA_MCXA366.wwdt_config_t (*C type*), 991
drivers_MCX_MCXA_MCXA366.WWDT_Deinit (*C function*), 989
drivers_MCX_MCXA_MCXA366.WWDT_Disable (*C function*), 989
drivers_MCX_MCXA_MCXA366.WWDT_Enable (*C function*), 989
drivers_MCX_MCXA_MCXA366.WWDT_FIRST_WORD_OF_REFRESH (*C macro*), 990
drivers_MCX_MCXA_MCXA366.WWDT_GetDefaultConfig (*C function*), 988

drivers_MCX_MCXA_MCXA366.WWDT_GetStatusFlags (*C function*), 989
drivers_MCX_MCXA_MCXA366.WWDT_Init (*C function*), 988
drivers_MCX_MCXA_MCXA366.WWDT_Refresh (*C function*), 990
drivers_MCX_MCXA_MCXA366.WWDT_SECOND_WORD_OF_REFRESH (*C macro*), 990
drivers_MCX_MCXA_MCXA366.WWDT_SetTimeoutValue (*C function*), 990
drivers_MCX_MCXA_MCXA366.WWDT_SetWarningValue (*C function*), 990
drivers_MCX_MCXA_MCXA366.WWDT_SetWindowValue (*C function*), 990